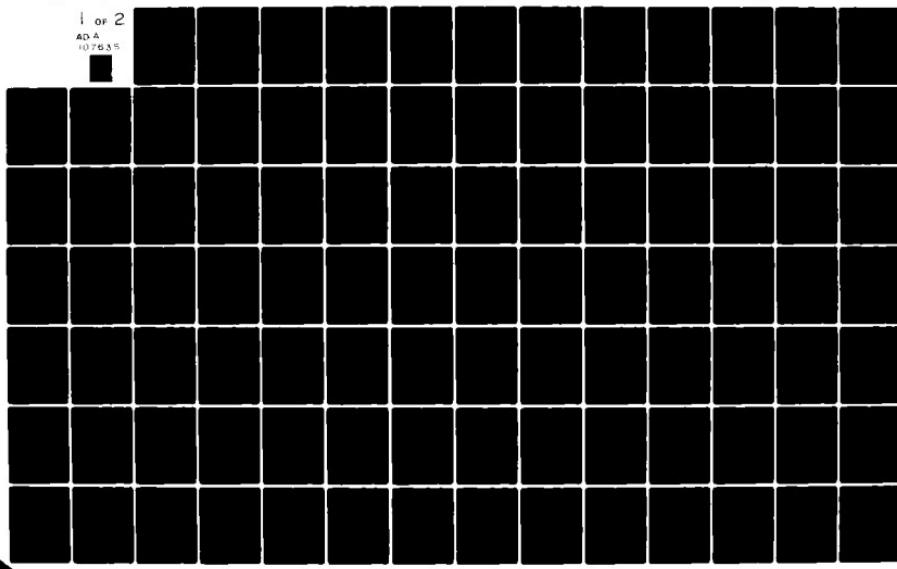


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THEORETICAL BASIS FOR CTABS80: A COMPUTER PROGRAM FOR THREE-DIMENSIONAL ANALYSIS OF BUILDING SYSTEMS

by

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September 1981
Final Report

A report under the Computer-Aided Structural Engineering (CASE) Project

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A



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| 20. ABSTRACT (Continue on reverse side if necessary and identify by block number) This report presents the theoretical basis for CTABS80, a computer program for the linear three-dimensional structural analysis of multistory frame and shear wall buildings subjected to static or dynamic loadings. | | |
| In CTABS80, the building is idealized as an assemblage of vertical independent frame and shear wall systems interconnected by horizontal floor diaphragms which are rigid in their own plane. The frame and shear wall systems must basically be of rectangular geometry (in elevation) with <i>(Continued)</i> → | | |

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20. ABSTRACT (Continued)

vertical columns (or piers) and horizontal beams (or spandrels). However, with special modeling techniques, very complex situations may be considered. A special shear panel element is developed to enable modeling of discontinuous shear walls and shear walls with arbitrary openings. A diagonal bracing system to model braced frames (X-braced, K-braced, or eccentrically braced systems) is also presented.

The column, shear panel, and diagonal formulations include the effects of bending, axial, and shear deformations. Bending and shear deformations are also included in the beam formulation; however, the effects of axial deformations are neglected.

The effects of the finite dimensions of the beams and columns on the stiffness of a frame or shear wall system are automatically included.

The buildings may be unsymmetrical and nonrectangular in plan. Torsional behavior and interstory compatibility are accurately reflected in the results.

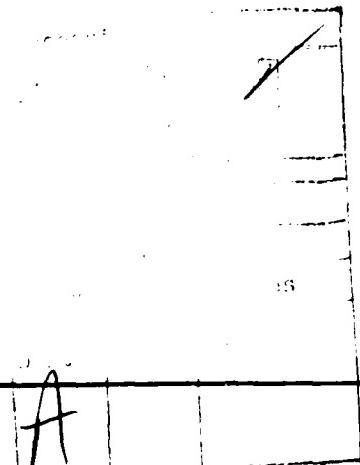
Four independent vertical and two independent lateral static load conditions are possible in any one run. These six static load conditions may be combined in any ratio to each other or to a lateral dynamic earthquake input which may be specified as a time-dependent ground acceleration or as an acceleration response spectrum.

Three-dimensional mode shapes and frequencies are evaluated.

The unique solution procedure used by CTABS80 considers the frame and shear walls as substructures, reduced with a modified wave front technique. This method results in a significant reduction in the program data preparation, computational effort, and storage requirements.

The consecutive levels of each of the individual frames can be arbitrarily connected to any (sequential by not necessarily consecutive) level of the structure, thereby making it possible for frames to bypass certain story levels. This option gives the program the capability to model partial diaphragms and multidiaphragms at any level.

A user's guide for the program is presented in Waterways Experiment Station Instruction Report K-81-9.



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PREFACE

This report presents the theoretical basis for a computer program called CTABS80 that can be used for static and dynamic analysis of multi-story frame and shear wall buildings. Dr. E. H. Wilson, University of California, Berkeley, was responsible for developing the original version of the program (TABS), sponsored mainly by a National Science Foundation Grant.

Modifications to the program to make it a more useful tool for Corps of Engineers' personnel were made by Mr. Ashraf Habibullah, Computers/Structures International, Oakland, Calif. His work was sponsored with funds provided to the Automatic Data Processing (ADP) Center, U. S. Army Engineer Waterways Experiment Station (WES), Vicksburg, Miss., by the Military Programs Directorate of the Office, Chief of Engineers, U. S. Army (OCE), under the Computer-Aided Structural Engineering (CASE) Project. This report and a companion user's guide for CTABS80 are the work of Dr. Wilson and Messrs. H. H. Dovey and Habibullah.

Specifications for the modifications to TABS were provided by the members of the CASE Task Group on Building Systems. The following were members of the Task Group (though all may not have served for the entire period) during the period of modifications to the program:

Mr. Dan Reynolds, Sacramento District (Chairman)
Mr. Jerry Foster, Baltimore District
Mr. Joseph Hartman, St. Louis District
Mr. David Illias, Portland District
Mr. Sefton Lucas, Memphis District
Mr. Jun Ouchi, Pacific Ocean Division
Mr. David Raisanen, North Pacific Division
Mr. Pete Rossbach, Baltimore District
Mr. James Simmons, Baltimore District
Mr. Ollie Werner, Middle East Division
Mr. Gene Wyatt, Mobile District

Dr. N. Radhakrishnan, Special Technical Assistant, ADP Center, WES, and CASE Project Manager, and Mr. Paul K. Senter, Computer-Aided Design Group (CADG), ADP Center, coordinated and monitored the work. Ms. Deborah K. Martin, CADG, supported the Task Group in changing the program to accept free-field input. Mr. Seymour Schneider, Military Programs Directorate, was the OCE point of contact. Mr. Donald L. Neumann was Chief, ADP Center.

Directors of WES during this period were COL J. L. Cannon, CE, COL N. P. Conover, CE, and COL T. C. Creel, CE. Technical Director was Mr. F. R. Brown.

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CONVERSION FACTORS, INCH-POUND TO METRIC (SI)
UNITS OF MEASUREMENT

Inch-pound units of measurement used in this report can be converted to metric (SI) units as follows:

| Multiply | By | To Obtain |
|--------------------------------|-----------|---------------------------|
| feet | 0.3048 | metres |
| inches | 2.54 | centimetres |
| kips (1000 lb force) | 4.448222 | kilonewtons |
| kips (force) per foot | 14.593904 | kilonewtons per metre |
| pounds (force) per square foot | 47.880263 | pascals |
| pounds (mass) per cubic foot | 16.01846 | kilograms per cubic metre |

THEORETICAL BASIS FOR CTABS80: A COMPUTER
PROGRAM FOR THREE-DIMENSIONAL ANALYSIS
OF BUILDING SYSTEMS

CHAPTER I: INTRODUCTION

A. Purpose

This report presents the theoretical basis for CTABS80, a computer program for the linear three-dimensional structural analysis of multistory frame and shear wall buildings subjected to static and dynamic loadings. A user's guide for the program is presented in Waterways Experiment Station (WES) Instruction Report K-81-9⁽¹⁸⁾.

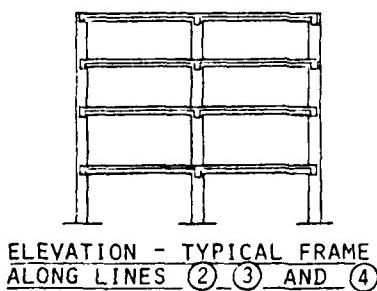
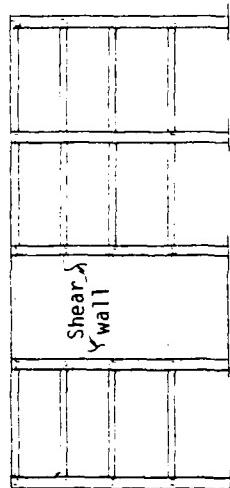
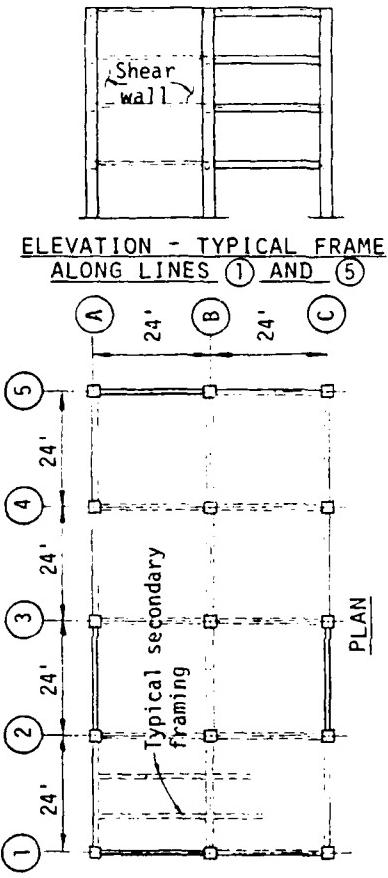
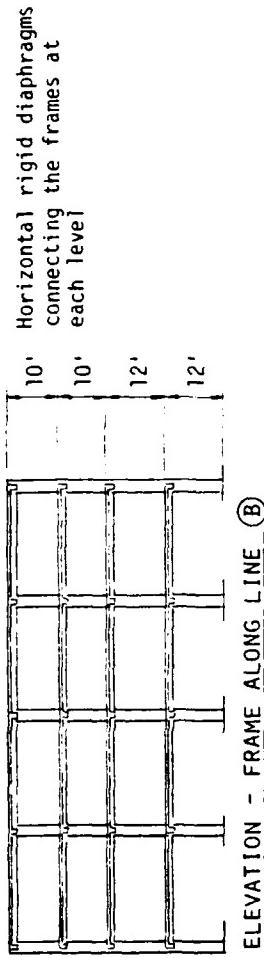
B. General-Purpose Programs for Structural Analysis

There are many two- and three-dimensional computer programs for the linear analysis of complex structures (1,2). Most of these programs can be used for the static and dynamic analysis of multistory frame and shear wall buildings. However, most of these programs do not give special recognition to the fact that building systems in themselves are a very special class of structures from an analytical point of view. The following are some of the characteristics that are inherent in the nature of a building analysis that a general-purpose analysis program may not recognize, thereby resulting in significant losses in man-hours, computer time, and possibly accuracy:

1. Most buildings are of simple geometry with horizontal beams and vertical columns. A simple rectangular grid can define such a geometry

vertical columns. A simple rectangular grid can define such a geometry with minimal input. See Figure 1.

2. Many of the frames and shear walls are typical. Most general-purpose programs do not recognize this fact; therefore, the input may be large, and some internal calculations may be unnecessarily duplicated.
3. The in-plane stiffnesses of the floor systems of most buildings are very high. General-purpose programs do not necessarily recognize this, resulting in a set of equilibrium equations which may be very large, and thereby causing an increase in computation effort by a factor of 10 to 100. Also, numerical errors may be introduced since the in-plane floor stiffnesses are several orders of magnitude greater than the story-to-story stiffnesses of the structure. Since these two stiffnesses are added in a direct stiffness approach, double precision may be required in the solution.
4. The loading in building systems is of a restricted form. Loads, in general, are either vertically down (dead or live) or lateral (wind or seismic). The vertical loads are usually applied on the beams, and the lateral loads are generated at the floor levels.
5. In many buildings, the dimensions of the members are large and have a significant effect on the stiffness of the frame. Therefore, corrections need to be applied to the member stiffnesses. Most general-purpose programs work on center-line dimensions, and stiffness corrections are usually very tedious to implement.
6. In the dynamic analysis of buildings, the mass of the structure can be accurately lumped at the floor levels. Recognizing this fact



NOTE /
Structure has 4 typical frames and 8 total frames

Figure 1. Typical frame and shear wall building

significantly reduces the size of the eigenvalue problem to be solved.

7. Various code loading requirements necessitate special options that allow convenient combinations of the vertical and lateral static and dynamic loadings. Also, the member forces need to be printed out at the support faces of the members. Such transformations are not automatic in general-purpose programs.
8. It is desirable to have a building analysis computer output printed in a special format; i.e., in terms of a particular frame, story, column, and beam. Also, special output such as story shears may be desirable.

In light of the above-mentioned and other reasons, the need for special-purpose programs for building analysis is apparent.

C. Special-Purpose Programs for Building Analysis

Various programs have been developed at the University of California at Berkeley for the linear analysis of multistory buildings in the past two decades (4,5,6). These programs have been used in the profession on many major structures in many different countries. One of the major reasons for the development of computer program TABS (1,2,3) was the direct "feedback" from the profession in the use of these programs.

The first of these programs, FRMSTC, is a static load analysis program for symmetrical buildings with parallel frames and shear walls. Lateral mode shapes and frequencies are also evaluated.

Program FRMDYN is the same as FRMSTC except that the load input is ground accelerations due to a specified earthquake. Time-dependent displacements and member forces are produced but are not combined with static loads.

Program LATERAL is an extension of FRMSTC to the static analysis of a system of frames and shear walls which are not parallel. Three degrees of freedom exist at each story level. This program does not have dynamic options.

The first version of TABS was released in 1972, with the intent of replacing the computer programs described above. CTABS80 is an enhanced version of the original version of TABS and is intended to supercede other enhanced versions such as XTABS and TABS77.

The computer program ETABS⁽¹⁵⁾ was released in 1975. The program allows three-dimensional frame input in which common column compatibility is enforced. The input data are more complex than those of TABS, and use of this program is only recommended if common column compatibility is important.

For buildings with other complexities, such as discontinuous or flexible diaphragms, sloped diaphragm, nonrectangular framing systems, etc., a general-purpose program such as SAPIV⁽¹²⁾ or EASE2⁽¹¹⁾ is still the most appropriate solution tool.

D. Disclaimer

Considerable time, effort, and expense have gone into the development and documentation of CTABS80, and the program has been thoroughly tested and used. In using the program, however, the user accepts and understands that no warranty is expressed or implied, either by the sponsors, the developers, or the distributors, as to the accuracy or the reliability of the program. The user must clearly understand the basic assumptions of the program and must verify his own results.

CHAPTER II: STRUCTURAL IDEALIZATION

An exact three-dimensional structural analysis is required for only a limited number of buildings. For the majority of buildings the following approximations can be made. These approximations greatly simplify the preparation of input data and significantly reduce the computational efforts associated with the analysis of the structure.

1. The structure is idealized as an assemblage of vertical planar "frames". A frame consists of m columns and $(m-1)$ beams. As long as shear and bending deformations are included in all members there is no need to distinguish between a shear wall/spandrel versus a beam/column system. See Figure 2.
2. The out-of-plane stiffnesses of all frames are assumed to be zero. Therefore each column at every floor has two degrees of freedom, a vertical displacement and a rotation. In addition, there is one lateral degree of freedom at every floor level of the frame.
3. Each floor is modeled as a horizontal diaphragm. This diaphragm is assumed to be infinitely stiff in-plane. The out-of-plane stiffness of this diaphragm is neglected. Bending stiffness of the floors may be included approximately in the modeling of the individual frames. It is apparent that axial deformation is not permitted in the beams. Floor levels must be the same for all frames. See Figure 2.
4. The floor diaphragm connects all the frames together at the corresponding level. The connection is only in a lateral sense. The frames otherwise are completely independent of each other. This also means that compatibility is not enforced with regard to

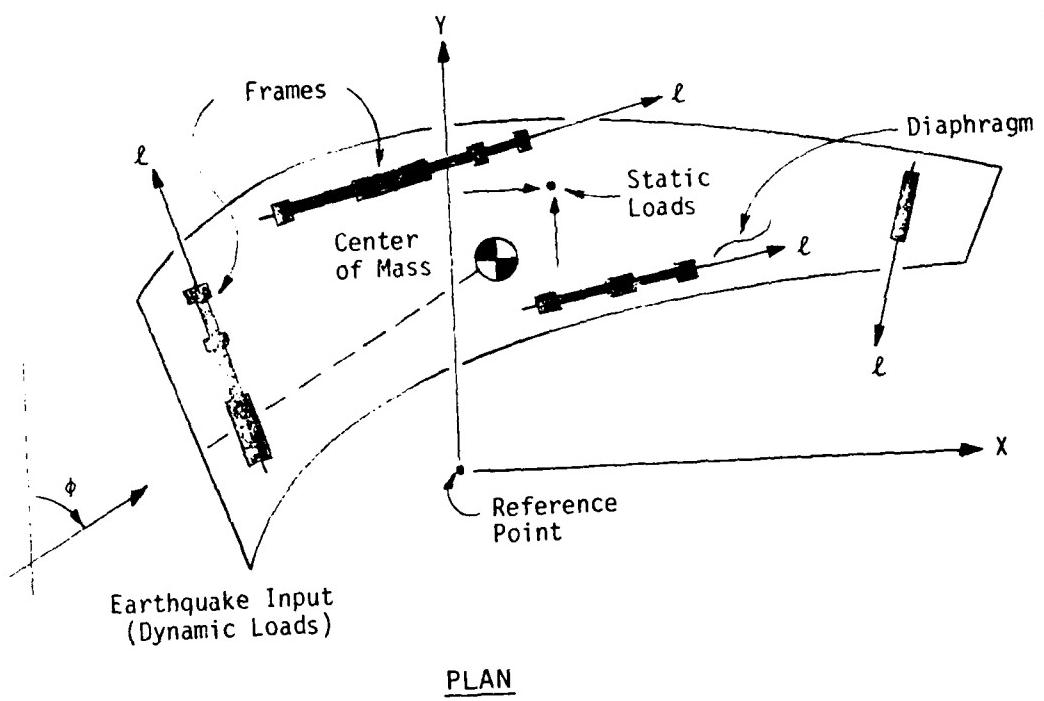


Figure 2. Typical story level

displacements at columns which are common to more than one frame. Thus axial deformations in common columns will not be the same. As for joint rotations, if the frames with common members are perpendicular in plan view, then the rotations are uncoupled. This assumption invalidates the program for use in the analysis of structures in which the tubular effect or common column compatibility is important.

5. Vertical loads are applied to each frame on a tributary area basis. The diaphragm will not transfer any vertical load from one frame to another. However, no frame can sidesway independently without engaging the other frames.
6. Lateral loads are applied as loads for the complete floor at each level. The loads are applied at specified locations on the floor diaphragms and get distributed to the various frames in accordance with their corresponding stiffnesses and locations.

A. The Frame Substructure

The elevation of a typical frame is shown in Figure 3. The frame is basically of rectangular geometry with vertical column center lines and horizontal floor levels as the basic reference lines for the description of the frame.

The frame is an assemblage of column, beam, panel, and bracing elements. Vertical loading is applied to the individual frames by means of loading patterns associated with each beam.

The column and beam elements have options for rigid offsets at each end to compensate for the effects of the finite dimensions of the members on

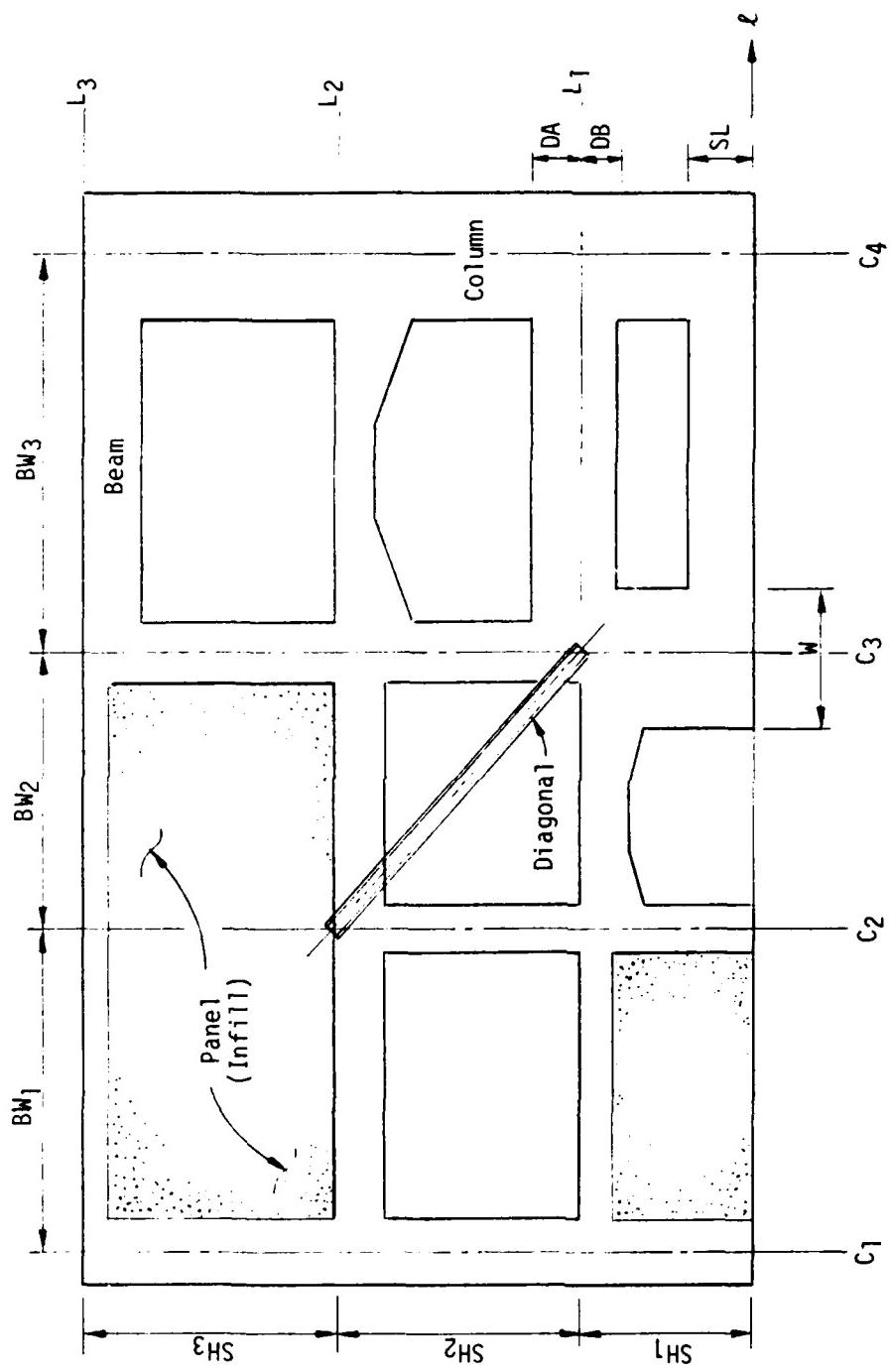


Figure 3. Elevation of typical frame

the stiffness of the system. The procedure used to set the lengths of these rigid offsets is presented later in this report.

(i). Individual Member Stiffnesses

The complete stiffness matrix of each frame is assembled by the direct stiffness technique. This involves calculating the local stiffness matrix, \underline{k} , for each member along with a transformation matrix, \underline{a} , which transforms the local displacements and forces, $\underline{\phi}$, \underline{S} , to global displacements and forces, \underline{r} , \underline{R}

$$\text{or: } \underline{\phi} = \underline{a} \underline{r} \quad \text{also: } \underline{S} = \underline{k} \underline{\phi}$$
$$\underline{S} = \underline{a} \underline{R} \quad \text{and: } \underline{R} = \underline{K} \underline{r}$$

where \underline{K} is the stiffness matrix in global coordinates.

Substituting $\underline{\phi} = \underline{a} \underline{r}$ and $\underline{S} = \underline{a} \underline{R}$ into $\underline{S} = \underline{k} \underline{\phi}$ we get:

$$\underline{a} \underline{R} = \underline{k} \underline{a} \underline{r}$$

Premultiply both sides by \underline{a}^T and recognizing $\underline{a}^T \underline{a} = \underline{I}$ we get:

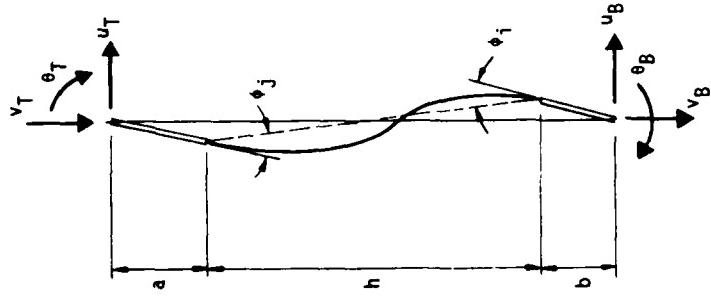
$$\underline{a}^T \underline{a} \underline{R} = \underline{a}^T \underline{k} \underline{a} \underline{r}$$

$$\underline{R} = \underline{a}^T \underline{k} \underline{a} \underline{r}$$

$$\text{As } \underline{R} = \underline{k} \underline{r} \text{ we get} \quad \underline{K} = \underline{a}^T \underline{k} \underline{a}$$

Thus knowing the local stiffness matrix \underline{k} and the coordinate transformation matrix \underline{a} the global stiffness matrix may be evaluated.

The \underline{a} and \underline{k} matrices for the column, beam, panel, and brace elements are presented in Figures 4, 5, 6, and 7, respectively.



$$\begin{Bmatrix} M_i \\ M_j \\ S \end{Bmatrix} = \begin{Bmatrix} s_a & s_b & 0 \\ s_b & s_a & 0 \\ 0 & 0 & s_c \end{Bmatrix} \begin{Bmatrix} \phi_i \\ \phi_j \\ \delta \end{Bmatrix}$$

FORCE/DEFORMATION TRANSFORMATION

$$\begin{Bmatrix} \phi_i \\ \phi_j \\ \delta \end{Bmatrix} = \begin{Bmatrix} 1 + \frac{b}{h} & \frac{1}{h} & \frac{a}{h} & -\frac{1}{h} & 0 & 0 \\ \frac{b}{h} & 1 + \frac{a}{h} & 1 + \frac{a}{h} & -\frac{1}{h} & 0 & 0 \\ 0 & 0 & 0 & 0 & 1 & -1 \end{Bmatrix} \begin{Bmatrix} \theta_B \\ u_T \\ \theta_T \\ u_T \\ v_B \\ v_T \end{Bmatrix}$$

DEFORMATION/DISPLACEMENT TRANSFORMATION

$$\phi_c = a_c \quad r_c$$

$$K_c = \begin{matrix} a^T & k_c & a_c \\ -a_c & - & - \end{matrix}$$

COLUMN STIFFNESS MATRIX
(6x6)

Figure 4

$$\begin{Bmatrix} M_i \\ M_j \end{Bmatrix} = \begin{bmatrix} s_a & s_b \\ s_b & s_a \end{bmatrix} \begin{Bmatrix} \phi_i \\ \phi_j \end{Bmatrix}$$

$$s_b = -k_b \quad \phi_b$$

FORCE/DEFORMATION TRANSFORMATION

$$\begin{Bmatrix} \phi_i \\ \phi_j \end{Bmatrix} = \begin{bmatrix} 1 + \frac{b}{L} & \frac{a}{L} & -\frac{1}{L} \\ \frac{b}{L} & 1 & 1 + \frac{a}{L} \\ \frac{a}{L} & 1 & 1 - \frac{1}{L} \end{bmatrix} \begin{Bmatrix} \theta_L \\ v_L \\ \theta_R \\ v_R \end{Bmatrix}$$

$$\phi_b = -\theta_b \quad \tau_b$$

DEFORMATION/DISPLACEMENT TRANSFORMATION

$$K_b = \begin{bmatrix} T & k_b & \theta_b \end{bmatrix}$$

BEAM STIFFNESS MATRIX
(4x4)

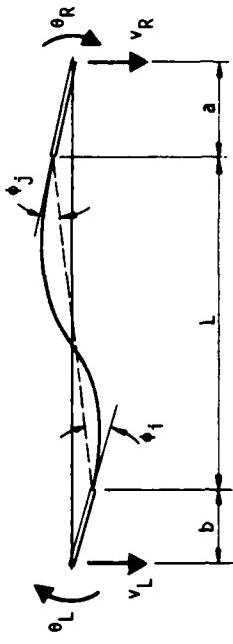
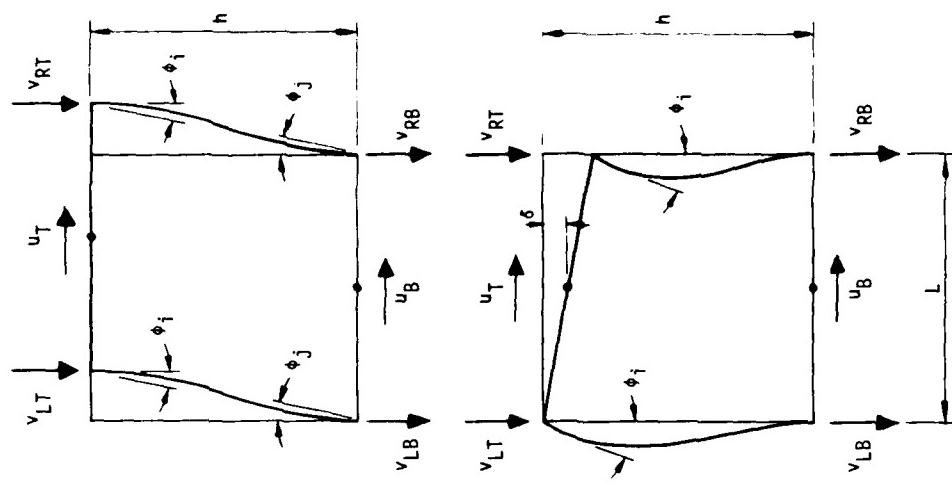


Figure 5



$$\begin{Bmatrix} M_i \\ M_j \\ S \end{Bmatrix} = \begin{Bmatrix} s_a & s_b & 0 \\ s_b & s_a & 0 \\ 0 & 0 & s_c \end{Bmatrix} \begin{Bmatrix} \phi_i \\ \phi_j \\ \delta \end{Bmatrix}$$

FORCE/DEFORMATION TRANSFORMATION

$$\begin{Bmatrix} \phi_i \\ \phi_j \\ \delta \end{Bmatrix} = \begin{Bmatrix} \frac{1}{h} & -\frac{1}{h} & -\frac{1}{L} & \frac{1}{L} & 0 & 0 \\ \frac{1}{h} & -\frac{1}{h} & 0 & 0 & -\frac{1}{L} & \frac{1}{L} \\ 0 & 0 & \frac{1}{2} & \frac{1}{2} & -\frac{1}{2} & -\frac{1}{2} \end{Bmatrix} \begin{Bmatrix} u_B \\ u_T \\ v_{LB} \\ v_{RT} \\ v_{RB} \\ v_{LT} \end{Bmatrix}$$

$$\phi_p = \underline{\underline{a}}_p \underline{\underline{r}}_p$$

DEFORMATION/DISPLACEMENT TRANSFORMATION

$$K_p = \underline{\underline{a}}_p^T \underline{\underline{k}}_p \underline{\underline{a}}_p$$

PANEL STIFFNESS MATRIX
(6x6)

Figure 6

$$\begin{Bmatrix} \mathbf{M}_i \\ \mathbf{M}_j \\ S \end{Bmatrix} = \begin{bmatrix} S_a & S_b & 0 \\ S_b & S_a & 0 \\ 0 & 0 & S_c \end{bmatrix} \begin{Bmatrix} \phi_i \\ \phi_j \\ \delta \end{Bmatrix}$$

$\underline{s}_D = k_D \underline{\phi}_D$

FORCE/DEFORMATION TRANSFORMATION

$$\begin{Bmatrix} \phi_i \\ \phi_j \\ \delta \end{Bmatrix} = \begin{bmatrix} 1 & \frac{h}{DD} & 0 - \frac{h}{DD} & \frac{L}{DD} - \frac{L}{DD} \\ 0 & \frac{h}{DD} & 1 - \frac{h}{DD} & \frac{L}{DD} - \frac{L}{DD} \\ 0 & -\frac{L}{D} & 0 - \frac{L}{D} & -\frac{h}{D} - \frac{h}{D} \end{bmatrix} \begin{Bmatrix} \theta_B \\ u_B \\ \theta_T \\ v_T \\ u_T \\ v_B \end{Bmatrix}$$

DEFORMATION/DISPLACEMENT MATRIX

$\underline{\phi}_D = \underline{\alpha}_D \underline{r}_D$

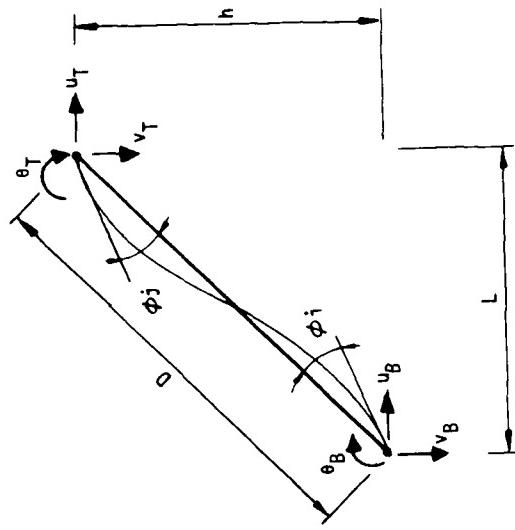


Figure 7

$$k_D = \underline{\alpha}_D^T k_D \underline{\alpha}_D$$

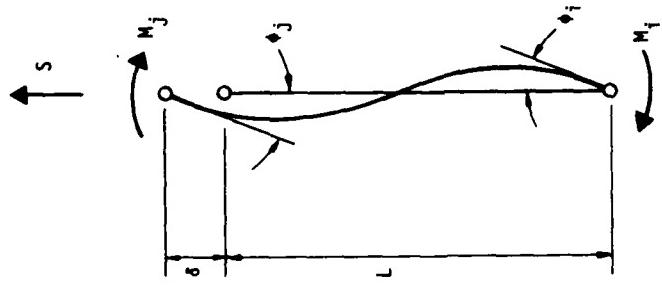
DIAGONAL (BRACE) STIFFNESS MATRIX
(6x6)

The column element formulation accounts for bending, axial and shear deformations. The basic stiffness matrix for such an element is shown in Figure 8. The column ends have options for rigid offsets. Figure 4 shows the six degrees of freedom associated with the column element and the deformation displacement transformation matrix linking the frame joint displacements to the column end deformations.

The beam element formulation is similar to that of the column except that the axial force component is dropped leaving a stiffness and transformation matrix as shown in Figure 5.

The panel element formulation is basically the same as that of the column except that each rotational degree of freedom is transformed into the two vertical displacements of the column lines bounding the panel element at each corresponding level. The axial degrees of freedom of the panel are also transformed as being an average of the vertical degrees of freedom of the two column lines bounding the panel element at each corresponding level. The degrees of freedom of the frame associated with the panel are therefore all translational. No rigid offsets are used. see Figure 6.

The diagonal element formulation is exactly the same as that of the column except that the brace is inclined and no rigid offsets are used. See Figure 7.



$$\begin{pmatrix} M_i \\ M_j \\ s \end{pmatrix} = \begin{bmatrix} S_a & S_b & 0 \\ S_b & S_a & 0 \\ 0 & 0 & S_c \end{bmatrix} \begin{pmatrix} \phi_i \\ \phi_j \\ \delta \end{pmatrix}$$

FORCE/DEFLECTION TRANSFORMATION

$$\text{Where: } S_a = \frac{2EI}{L} \left(\frac{2 + \frac{\beta}{1 + 2\beta}}{1 + 2\beta} \right)$$

$$S_b = \frac{2EI}{L} \left(\frac{1 - \frac{\beta}{1 + 2\beta}}{1 + 2\beta} \right)$$

$$S_c = \frac{AE}{L}$$

$$\beta = \frac{6EI}{L^2 \bar{A} G}$$

A = axial area

\bar{A} = effective shear area

I = moment of inertia

E = elastic modulus

G = shear modulus

L = length

FLEXURAL MEMBER WITH AXIAL DEFORMATIONS

Figure 8

The complete stiffness matrix for each frame has two degrees of freedom for each beam-column intersection and one lateral degree of freedom per story.

(ii). Lateral Frame Stiffness

With the frame degrees of freedom appropriately ordered, the frame equilibrium equations have the form shown in Figure 9 . Where N is the number of stories in the frame, \underline{r}_N is the vector of joint displacements (that is vertical displacement and rotation) at story level n and \underline{r}_L is the vector of lateral story displacements. Lateral loads are applied to the complete structure and are considered when the lateral stiffness matrix for the complete building is assembled. Gaussian elimination is performed on the full system up to and including the equations:

$$\underline{R}_N = \underline{C}_{N-1} \underline{r}_{N-1} + \underline{K}_N \underline{r}_N + \underline{E}_N \underline{r}_L$$

The last N equations (\underline{r}_L is a vector of order N) may now be written as:

$$\underline{R}_L = \underline{K}_L \underline{r}_L$$

The vector \underline{R}_L is the lateral load submatrix of the frame and is modified by the elimination process due to vertical loading on the frame. These terms represent the sidesway effects under vertical loading. The matrix \underline{K}_L clearly represents the frame lateral stiffness matrix; i.e., the stiffness matrix of the frame in terms of only the lateral story displacements.

Within the computer program the following approach is adopted in order to reduce storage requirements. The assembly and reduction process is

| SIZE | | | | | |
|-------------------------------|---|---|-----------------------|-----------------------|------|
| \underline{R}_1 | $\underline{K}_1 \quad \underline{C}_1$ | | \underline{E}_1 | \underline{r}_1 | 2NC |
| \underline{R}_2 | $\underline{C}_1^T \quad \underline{K}_2 \quad \underline{C}_2$ | | \underline{E}_2 | \underline{r}_2 | 2NC |
| \underline{R}_3 | $\underline{C}_2^T \quad \underline{K}_3 \quad \underline{C}_3$ | | \underline{E}_3 | \underline{r}_3 | 2NC |
| . | . | . | . | . | |
| \underline{R}_n | $\underline{K}_n \quad \underline{C}_n$ | | \underline{E}_n | \underline{r}_n | 2NC |
| \underline{R}_{n+1} | $\underline{C}_n^T \quad \underline{K}_{n+1}$ | | \underline{E}_{n+1} | \underline{r}_{n+1} | 2NC |
| . | . | . | . | . | |
| \underline{R}_{N-1} | | $\underline{K}_{N-1} \quad \underline{C}_{N-1} \quad \underline{E}_{N-1}$ | | \underline{r}_{N-1} | 2NC |
| \underline{R}_N | | $\underline{C}_{N-1}^T \quad \underline{K}_N \quad \underline{E}_N$ | | \underline{r}_N | 2NC |
| $\underline{\underline{R}_L}$ | $\underline{E}_1^T \quad \underline{E}_2^T \quad \dots \quad \underline{E}_n^T \quad \underline{E}_{n+1}^T \quad \dots \quad \underline{E}_{N-1}^T \quad \underline{E}_N^T$ | | \underline{K}_L | \underline{r}_L | NS+1 |

The equations in core at any one time are blocked out above.

NC = No. of Column Lines NS = No. of Stories

Figure 9. Complete equation system of frame substructure

carried out systematically story by story from the top of the structure such that at any level, n , we consider the system shown below:

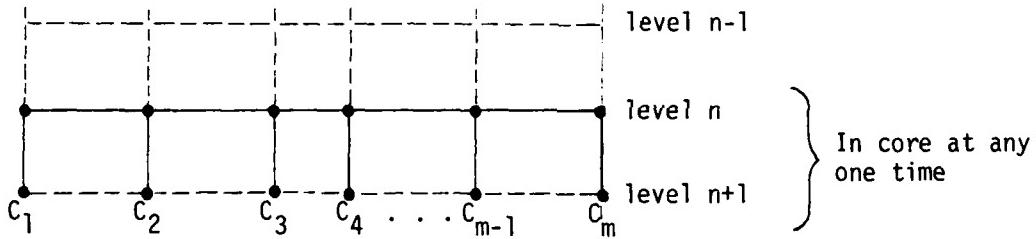
$$\begin{Bmatrix} R'_n \\ R'_{n+1} \\ \vdots \\ R'_L \end{Bmatrix} = \begin{bmatrix} K'_n & C'_n & E'_n \\ C'^T_n & K'_{n+1} & E'_{n+1} \\ E'^T_n & E'^T_{n+1} & K'_L \end{bmatrix} \begin{Bmatrix} r_n \\ r_{n+1} \\ \vdots \\ r_L \end{Bmatrix}$$

where the prime indicates that the submatrices may have been modified by previous elimination.

At each level the following steps are performed:

- Add in the individual member stiffnesses for level n .

These are shown below:



- Perform the elimination on the equations of the uppermost partition in the equations above
- Save these reduced equations for subsequent back-substitution.
- Rearrange the submatrices in the equation above appropriately in order to proceed to the next level. This rearrangement is as follows:

$$\begin{Bmatrix} R'_{n+1} \\ 0 \\ R'_L \end{Bmatrix} = \begin{bmatrix} K'_{n+1} & 0 & E'_{n+1} \\ 0 & 0 & 0 \\ E'^T_{n+1} & 0 & K'_L \end{bmatrix} \begin{Bmatrix} r_{n+1} \\ r_{n+2} \\ r_L \end{Bmatrix}$$

e. Repeat the above steps for the next level. Thus after the elimination is completed for joint displacements at all story levels, we are left with the lateral stiffness matrix for the frame.

(iii). Rigid Joint Offset For Beams and Columns

The deformations within the joint, an area bounded by the finite dimensions of any beam and column intersection (shown shaded in Figure 10) are neglected. In other words, this area is assumed to be an infinitely rigid rectangular diaphragm.

This is achieved by providing rigid offsets at the ends of the beams equal in length to one half of the widths of the column below at each corresponding end. Rigid offsets are also provided at each end of the columns equal to the depth of the larger of the beams on either side of the column at the corresponding level.

It has been found that, in general, a reduction in the lengths of the rigid offsets to compensate for some deformation that may exist in the joint is justifiable and gives better results, especially in cases where the member dimensions are substantial. See Reference 9.

Reduction of the rigid link dimension has been coupled to the size of the member. In other words, the rigid link is calculated as described above and then is reduced by 25% of the dimension of the member, at each end.

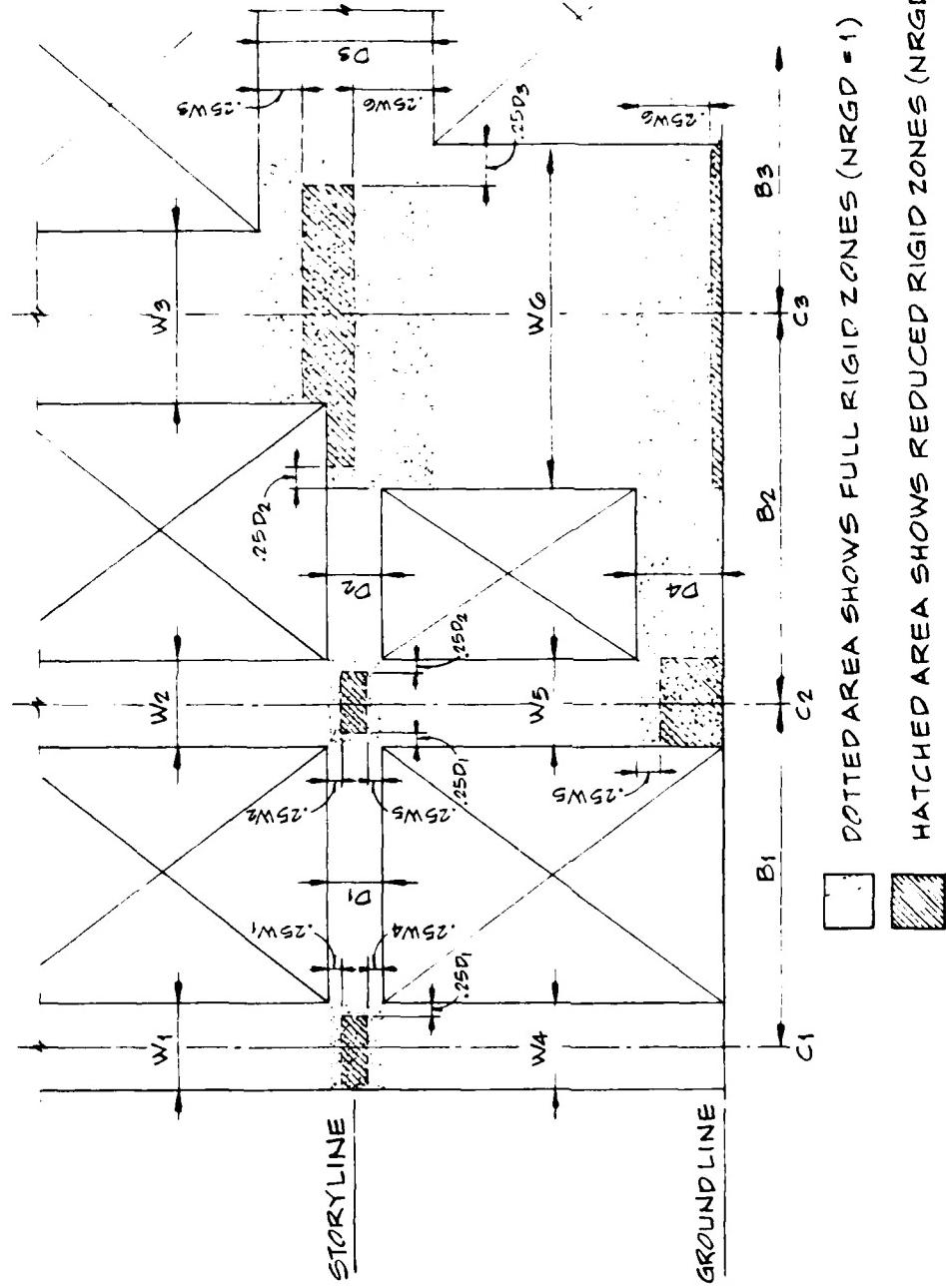


Figure 10. Illustration of rigid zone reduction methodology

Thus the beam rigid links are reduced by 25% of the beam depth and the column rigid links are reduced by 25% of the column width at each end. The reduction cannot, of course, result in a negative rigid link length. This reduction procedure is optional. If no column widths or beam lengths are input the rigid link lengths degenerate to zero and the analysis is carried out on the frame grid line basis.

B. The Complete Structure

In order to combine the frame lateral stiffness matrices into a complete structure lateral stiffness matrix, each of the frame stiffnesses must be transformed to a common displacement coordinate system (which will be referred to as the global system). The global system chosen is two translations and one rotation per story. The origin of these global displacement coordinates at each story level is taken at the center of mass of that story segment. This position may vary from story to story. Such a formulation will degenerate the mass matrix to a diagonal form, thus simplifying the eigen-value problem in the dynamics.

The first step is to develop the transformation between the frame lateral displacements and the global displacements. With reference to Figure 11, the transformation at any level, n, is as follows:

$$r_{Ln} = \begin{pmatrix} \cos\alpha & \sin\alpha & -d_n \end{pmatrix} \begin{Bmatrix} r_{xn} \\ r_{yn} \\ r_{\theta n} \end{Bmatrix}$$

or: $r_{Ln} = a_n r_n$

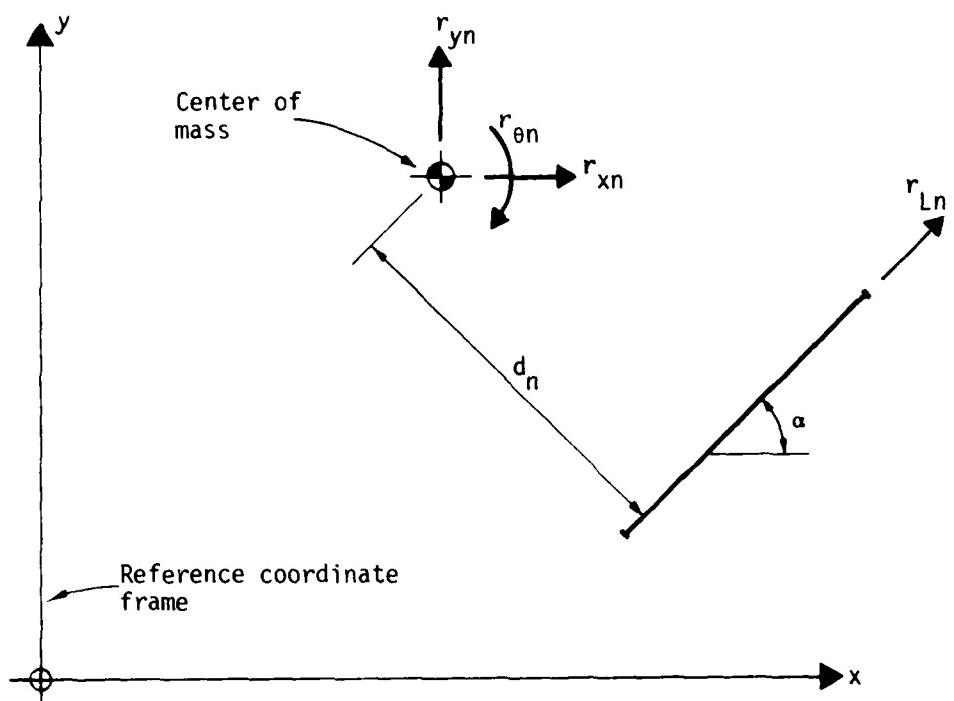


Figure 11. Structural global lateral displacements
and frame local lateral displacements

Assembling the transformations for all floors, we obtain the complete transformation between frame lateral displacements and global displacement as follows:

$$\begin{pmatrix} r_{L1} \\ r_{L2} \\ \vdots \\ r_{Ln} \\ \vdots \\ r_{LN} \end{pmatrix} = \begin{pmatrix} a_1 \\ a_2 \\ \vdots \\ a_n \\ \vdots \\ a_N \end{pmatrix} \quad \begin{pmatrix} r_1 \\ r_2 \\ \vdots \\ r_n \\ \vdots \\ r_N \end{pmatrix}$$

or:

$$r_{Li} = A_i r$$

r is the complete vector of global displacements. The frame lateral stiffness is transformed to the global system and becomes:

$$K_i = A_i^T K_{Li} A_i$$

where the subscript i denotes the i th frame.

The structure lateral stiffness is assembled by the addition of components from all frames: i.e.,

$$K = \sum_i K_i$$

The frame lateral load vector from sidesway effects must also be transformed to the global system. This transformation is shown by:

$$R_i = A_i^T R'_{Li}$$

The global load vector is formed by the summation of frame sway effects and the addition of externally applied lateral loads \underline{F} , i.e.:

$$\underline{R} = \sum_i \underline{R}_i + \underline{F}$$

The global forces \underline{F} are specified; however, they are also given by:

$$\underline{F} = \sum_i \underline{A}_i^T \underline{P}_{Li}$$

Expanding the tri-matrix product:

$$\underline{K}_i = \underline{A}_i^T \underline{K}_{Li} \underline{A}_i$$

we get:

$$\begin{bmatrix} K_{11} & K_{12} & \dots & \dots & \dots \\ K_{21} & K_{22} & \dots & \dots & \dots \\ \vdots & \vdots & \ddots & \ddots & \ddots \\ \vdots & \vdots & K_{ij} & \ddots & \ddots \\ \vdots & \vdots & \ddots & \ddots & \ddots \\ \vdots & \vdots & \ddots & \ddots & K_{NN} \end{bmatrix} = \begin{bmatrix} \underline{a}_1^T \\ \underline{a}_2^T \\ \vdots \\ \vdots \\ \vdots \\ \underline{a}_N^T \end{bmatrix} \begin{bmatrix} k_{11} & k_{12} & \dots & \dots \\ \vdots & \vdots & \ddots & \ddots \\ \vdots & \vdots & \ddots & k_{NN} \\ \vdots & \vdots & \ddots & \ddots \\ \vdots & \vdots & \ddots & \ddots \\ \vdots & \vdots & \ddots & \ddots \end{bmatrix} \begin{bmatrix} \underline{a}_1 \\ \underline{a}_2 \\ \vdots \\ \vdots \\ \vdots \\ \underline{a}_N \end{bmatrix}$$

It is worth noting that a typical 3×3 submatrix K_{ij} within \underline{K}_i has the form $\underline{a}_i^T \underline{k}_{ij} \underline{a}_j$. Obviously this product may be formed independently for each term in and added directly into \underline{K} . Hence the global equilibrium equations are formed.

$$\underline{R} = \underline{K} \underline{r}$$

It may be noted that the global stiffness \underline{K} is a full matrix, but it is of course relatively small compared to the total number of degrees of freedom associated with all the frames in the structure.

CHAPTER III: STATIC ANALYSIS

The static analysis equations:

$$R = k r$$

are solved directly by Gaussian elimination giving a vector of global lateral displacements, r . Next, for each frame, the lateral displacements, r_{Li} are computed using:

$$r_{Li} = A_i r$$

To complete the solution for each frame, the following system is considered.

$$R'_n = \begin{bmatrix} K'_n & C'_n & E'_n \end{bmatrix} \begin{bmatrix} r_n \\ r_{n+1} \\ r_L \end{bmatrix}$$

Note that these are the equations which were reduced, then saved at each level, n , of the frame. That is, K'_n was triangularized. At any stage, n , r_{n+1} and r_L are known and so r_n is computed by back substitution.

To start this sequence, we simply note that for $n = N$ (the number of stories in the structure) r_{N+1} represents the displacements at the foundation which are zero since columns are assumed rigidly connected to the foundation. Thus the frame joint displacements are computed successively story by story and individual member forces may be computed at the same time from the force/deformation transformations previously presented.

A. Vertical Loads Analysis

The vertical loads are applied on each individual frame as beam span loads.

Four independent vertical loading conditions are possible. The self weight of the frames can be automatically calculated by the program and added to the load vector of the first load condition. Typically the first load condition is used for the dead load analysis of the structure; the second load condition is used for the live load analysis of the structure. The third and fourth load conditions may be used for skip live loading or left unused.

B. Lateral Load Analysis

The lateral static loads are applied as forces acting at a particular point on each floor level. Two independent lateral loading conditions are possible. The lateral loads may be due to wind or earthquake. The wind loads have to be calculated and input by the user, based upon the wind pressure and the exposed tributary area of the building at each level of the structure. The seismic static equivalent loads may be automatically calculated by the program, based upon the requirement of Reference 14. The modal participation factors calculated by the program are used to determine the predominant directions of the modes and the time periods of the predominant modes are used in calculating the seismic loads in the corresponding directions.

The program has options to calculate the dynamic properties, such as the mass and mass moment of inertia of each floor level based upon simplified user input.

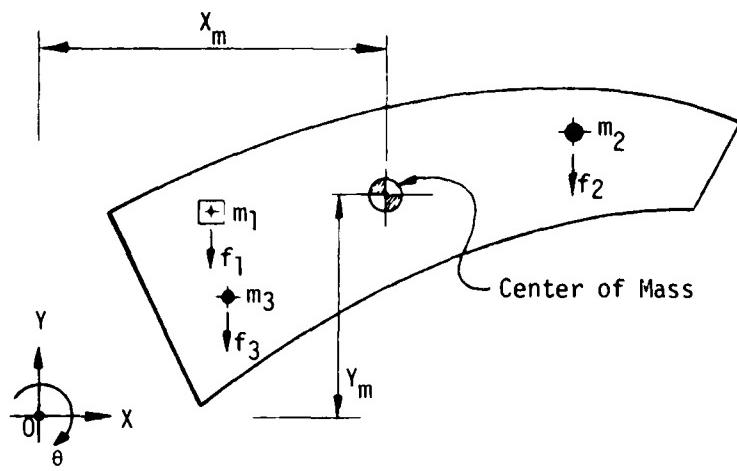
CHAPTER IV: DYNAMIC ANALYSIS

The exact formulation of the dynamic response of a structure involves an infinite number of degrees of freedom. For most structures, however, the response may be adequately captured by a limited number of discrete points (or joints) within the system. In the buildings considered here, the response may be described by the lateral motions of each floor level, as previously described for the formation of the lateral structure stiffness matrix. The center of mass is used as the master constraint location at each level in the generation of the lateral stiffness matrix. The tributary mass of each story level is lumped at the center of mass of the level along with the mass moment of inertia of the floor about a vertical axis through the center of mass to compensate for the rotational aspects of the lumping process. The resulting mass matrix is of diagonal form. With this lumped parameter idealization, equilibrium of the structure is described by a set of ordinary second order differential equations.

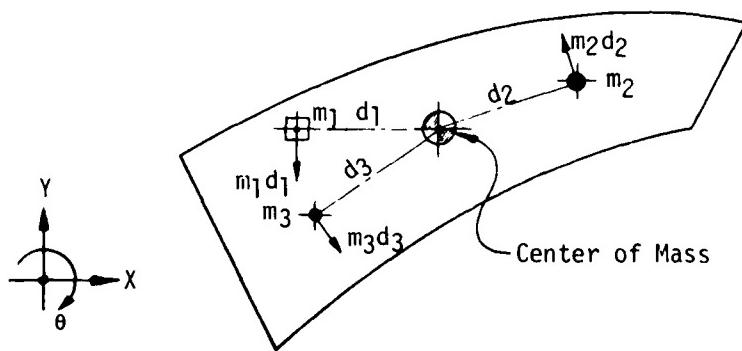
A. Mass Approximation, Mass and Mass Moment of Inertia

In the diaphragm shown in Figure 12, there are various lumped masses ($m_1, m_2, m_3 \dots$ etc.) and other distributed masses associated with the diaphragm level.

When the diaphragm is subjected to a unit translational acceleration in the Y-direction, inertia forces opposing the direction of the acceleration will be generated, i.e. $f_1 = m_1 \times 1, f_2 = m_2 \times 1, f_3 = m_3 \times 1 \dots$. The resultant of all these forces and line of action of the resultant can be determined. The magnitude of the resultant is found to be $= f_1 +$



(a) DEFINITION OF MASS AND CENTER OF MASS



(b) DEFINITION OF MASS MOMENT OF INERTIA

Figure 12

$f_2 + f_3 \dots = m_1 + m_2 + m_3 \dots$ = total mass associated with the diaphragm. The resultant is parallel to the Y-direction and passes through a point at a distance X_m from 0.

Similarly, a unit translation in the X-direction will give a resultant of the same magnitude but parallel to the X-direction and passing through a point a distance Y_m from 0.

The coordinates X_m , Y_m define the location of a point known as the center of mass.

Redefining the term, Mass: "The mass of a diaphragm may be defined as the force generated when the center of mass of the diaphragm undergoes a unit translational acceleration. This force acts at the center of mass, resulting in no associated moment."

$$\text{Mass} = \sum_{i=1}^n m_i$$

Similarly, defining the term, Mass Moment of Inertia (or Rotational Mass): "The mass moment of inertia of a diaphragm may be defined as the moment generated when the center of mass of the diaphragm undergoes a unit rotational acceleration about a vertical axis. No resultant translational force is associated with the couple."

The radial distances from the center of mass of the lumped masses $m_1, m_2, m_3 \dots$ are $d_1, d_2, d_3 \dots$ respectively, as shown in Figure 12.

Due to a unit rotational acceleration of the center of mass about a vertical axis, $m_1, m_2, m_3 \dots$ will have translational accelerations of $d_1x_1, d_2x_1, d_3x_1 \dots$ Thereby giving corresponding inertia forces of

$m_1 d_1, m_2 d_2, m_3 d_3 \dots$. The moments of these forces about a vertical axis through the center of mass are $m_1 d_1^2, m_2 d_2^2, m_3 d_3^2 \dots$.

$$\therefore MMI = m_1 d_1^2 + m_2 d_2^2 + m_3 d_3^2 \dots$$

$$= \sum_{i=1}^n m_i d_i^2$$

= Polar Moment of Inertia of all Masses, about a vertical axis through the center of mass

B. Dynamic Equilibrium Equations

The equilibrium equations for a structure, including dynamic effects, may be written in the following form:

$$\underline{M} \ddot{\underline{r}}_a + \underline{C} \dot{\underline{r}} + \underline{K} \underline{r} = \underline{P}(t) \quad \dots \dots \dots \quad (a)$$

where: \underline{M} = mass matrix

\underline{C} = damping matrix

\underline{K} = stiffness matrix

$\underline{P}(t)$ = applied load vector, which may be time dependent

\underline{r} = displacement vector of deformation relative to support motion

$\ddot{\underline{r}}_a$ = absolute acceleration vector

\underline{r} and \underline{r}_a are related in the following fashion:

$$\underline{r}_a = \underline{v}_g + \underline{r}$$

where \underline{v}_g is the vector of pseudo-static displacements due to support movement. Also:

$$\ddot{\underline{r}}_a = \ddot{\underline{v}}_g + \ddot{\underline{r}}$$

These vectors have the following form for a typical floor, of a building shown in Figure 13.

$$\begin{Bmatrix} r_{xa} \\ r_{ya} \\ r_{\theta a} \end{Bmatrix}_n = \begin{Bmatrix} v_{gx} \\ v_{gy} \\ v_{g\theta} \end{Bmatrix} + \begin{Bmatrix} r_{xn} \\ r_{yn} \\ r_{\theta n} \end{Bmatrix} = \begin{Bmatrix} \sin \beta \\ \cos \beta \\ 0 \end{Bmatrix} \underline{v}_g + \begin{Bmatrix} r_{xn} \\ r_{yn} \\ r_{\theta n} \end{Bmatrix}$$

and:

$$\begin{Bmatrix} \ddot{r}_{xa} \\ \ddot{r}_{ya} \\ \ddot{r}_{\theta a} \end{Bmatrix}_n = \begin{Bmatrix} \sin \beta \\ \cos \beta \\ 0 \end{Bmatrix} \ddot{\underline{v}}_g + \begin{Bmatrix} \ddot{r}_{xn} \\ \ddot{r}_{yn} \\ \ddot{r}_{\theta n} \end{Bmatrix}$$

i.e.:

$$\underline{r}_{na} = \underline{b} \underline{v}_g + \underline{r}_n$$

Or, for all floors:

$$\underline{r}_a = \underline{B} \underline{v}_g + \underline{r}$$

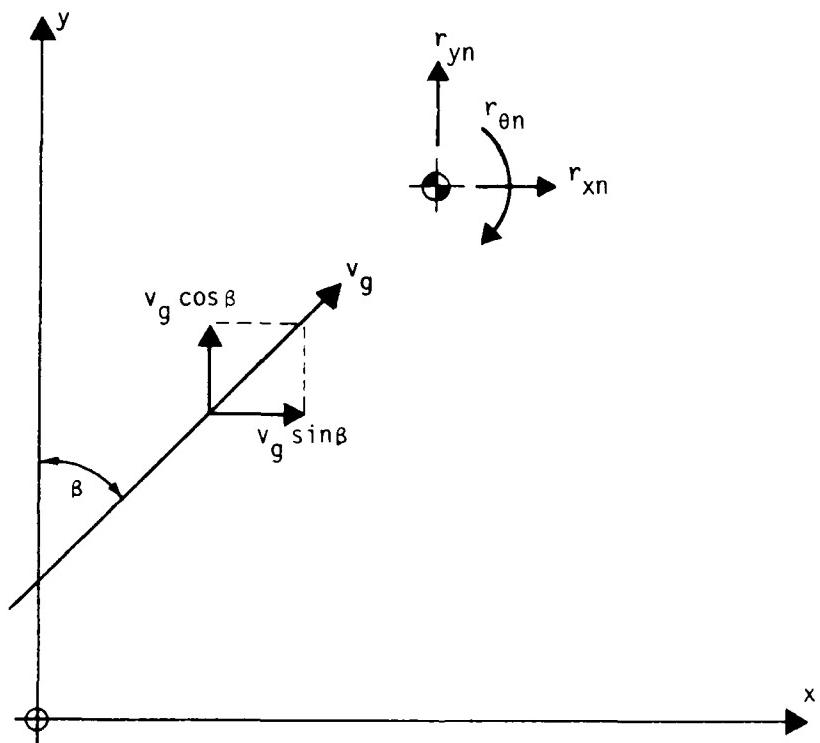


Figure 13. Ground and structural displacements

where:

$$\underline{B} = \begin{Bmatrix} b_1 \\ b_2 \\ b_3 \\ \vdots \\ b_N \end{Bmatrix}; \quad b_1 = b_2 \text{ etc.}$$

In the case of seismic analysis, there are no externally applied loads; i.e., $P(t) = 0$. Then equation (a) may be written as:

$$\underline{M}(\ddot{\underline{r}} + \underline{B}\ddot{\underline{v}}_g) + \underline{C}\dot{\underline{r}} + \underline{K}\underline{r} = \underline{0}$$

or:

$$\underline{M}\ddot{\underline{r}} + \underline{C}\dot{\underline{r}} + \underline{K}\underline{r} = -\underline{M}\underline{B}\ddot{\underline{v}}_g \quad \dots \dots \dots \quad (b)$$

This coupled set of equations may be solved simultaneously with an appropriate numerical technique. Another approach, which will be used here, is to find a transformation which uncouples the equations so that they may be solved independently. This transformation, of course is via the eigen-vectors or mode shapes of the system.

C. Mode Shapes and Frequencies

The vibration mode shapes represent the solution of the undamped free vibration problem given by:

$$\underline{M}\ddot{\underline{r}} + \underline{K}\underline{r} = \underline{0}$$

The eigen-value problem to be solved is written as:

$$\underline{K} \underline{\phi} = \underline{\omega}^2 \underline{M} \underline{\phi}$$

where: $\underline{\phi}$ = mode shapes

$\underline{\omega}$ = frequencies

The mode shapes are normalized such that:

$$\underline{\phi}^T \underline{M} \underline{\phi} = \underline{I}$$

then also:

$$\underline{\phi}^T \underline{K} \underline{\phi} = \underline{\omega}^2$$

Also, it is assumed that the damping matrix \underline{C} is of a form that is uncoupled by the mode shapes; specifically it is assumed that:

$$\underline{\phi}^T \underline{C} \underline{\phi} = [2\lambda_m \quad \omega_m]$$

so that λ_m represents the damping of the m th mode.

The actual displacements, \underline{r} , are now expressed as a linear combination of the mode shapes.

$$\underline{r} = [\underline{\phi}_1 \quad \underline{\phi}_2 \quad \underline{\phi}_3 \dots \underline{\phi}_N] \begin{bmatrix} z_1(t) \\ z_2(t) \\ \vdots \\ z_N(t) \end{bmatrix} \dots (c)$$

i.e.:

$$\underline{r} = \underline{\phi} \underline{z}$$

also

$$\dot{\underline{r}} = \underline{\phi} \dot{\underline{z}}$$

and:

$$\ddot{\underline{r}} = \underline{\phi} \ddot{\underline{z}}$$

where $\underline{z}_m(t)$ represents the response of the m th mode.

D. Time History Analysis

Using equations (b), equation (c) may be rewritten as:

$$\underline{M} \underline{\phi} \ddot{\underline{z}} + \underline{C} \underline{\phi} \dot{\underline{z}} + \underline{K} \underline{\phi} \underline{z} = - \underline{M} \underline{B} \ddot{\underline{v}}_g$$

Premultiplication by $\underline{\phi}^T$ yields the uncoupled set of second order equations:

$$\underline{M}^* \ddot{\underline{z}} + \underline{C}^* \dot{\underline{z}} + \underline{K}^* \underline{z} = \underline{P}^* \ddot{\underline{v}}_g$$

where:

$$\underline{M}^* = \underline{\phi}^T \underline{M} \underline{\phi} = \underline{I}$$

$$\underline{C}^* = \underline{\phi}^T \underline{C} \underline{\phi} = [2\lambda_m \omega_m]$$

$$\underline{K}^* = \underline{\phi}^T \underline{K} \underline{\phi} = [\omega_m^2]$$

$$\underline{P}^* \ddot{\underline{v}}_g = \underline{\phi}^T \underline{M} \underline{B} \ddot{\underline{v}}_g$$

to find the form of \underline{P}^* , consider:

$$\underline{M} \underline{B} = \begin{bmatrix} m_1 & & & & \\ & m_1 & & & \\ & & J_1 & & \\ & & & m_2 & \\ & & & & J_2 \\ & & & & \\ & & & & \\ & & & & J_N \end{bmatrix} \quad \left\{ \begin{array}{c} \sin\beta \\ \cos\beta \\ 0 \\ \sin\beta \\ \cos\beta \\ 0 \\ \vdots \\ 0 \end{array} \right\}$$

where: m_1 = mass of story 1

J_1 = rotational mass moment of inertia of story 1

i.e.:

$$\underline{M} \underline{B} = \begin{bmatrix} m_1 \sin\beta \\ m_1 \cos\beta \\ 0 \\ m_2 \sin\beta \\ m_2 \cos\beta \\ 0 \\ \vdots \\ \vdots \end{bmatrix}$$

So, a typical term of \underline{P}_m^* has the form:

$$P_m^* = \underline{\phi}_m^T \underline{M} \underline{B}$$

$$= <\phi_{1x} \phi_{1y} \phi_{1\theta} \phi_{2x} \phi_{2y} \phi_{2\theta} \dots> \begin{bmatrix} m_1 \sin\beta \\ m_1 \cos\beta \\ 0 \\ m_2 \sin\beta \\ m_2 \cos\beta \\ 0 \\ \vdots \\ \vdots \end{bmatrix}$$

$$P_m^* = \sum_{n=1}^N m_n \{ \sin\beta \phi_{nx} + \cos\beta \phi_{ny} \}$$

Now a typical equation governing the response in the m th mode has the form:

$$\ddot{z}_m + 2\lambda_m \omega_m \dot{z}_m + \omega_m^2 z_m = p_m^* \ddot{v}_g \quad \dots \dots \dots \quad (d)$$

For any earthquake, the ground acceleration, \ddot{v}_g is specified as a set of discrete values and linear interpolation is used for intermediate values. On any linear portion then:

$$\ddot{v}_g = A + Bt$$

where A and B are computed from the end values as shown in Figure 14.

On any linear segment t_1, t_2 then:

$$\ddot{z}_m + 2\lambda_m \omega_m \dot{z}_m + \omega_m^2 z_m = p_m^* (A + Bt)$$

The solution to this equation is summarized in Figure 14.

At rest initial conditions are used for the first linear portion. The values of displacement and velocity at the end of any linear portion form the initial conditions for the following linear segment and so on. Repetition gives the complete solution over the required time span. With solutions for each mode, equation (c) is used to give a set of structure displacements r at each output time step.

The backsubstitution procedure used for the time history analysis is exactly the same as that described for the static analysis in Chapter III. Backsubstitution for each time step is equivalent to one static load backsubstitution. The frame displacements and member forces are determined at each time step and the maxima of these parameters over the time span are output as dynamic load condition 3.

For the equation: $\ddot{z}_m + 2\lambda_m \omega_m \dot{z}_m + \omega_m^2 z_m = P_m^* (A + Bt)$

On any linear segment such as t_1, t_2 , the solution is given by:

$$\begin{aligned} \ddot{z}_m(t) &= P_m^* e^{-\lambda_m \omega_m t} \left\{ \left[z_m(t_1) - \frac{A}{2} + \frac{2\lambda_m B}{\omega_m} \right] \cos \omega_{Dm} t \right. \\ &\quad \left. + \frac{1}{\omega_{Dm}} \left[z_m(t_1) + \lambda_m \omega_m z_m(t_1) - \frac{\lambda_m A}{\omega_m} + \frac{B(2\lambda_m^2 - 1)}{\omega_m^2} \right] \sin \omega_{Dm} t \right\} \\ &\quad + P_m^* \left[\frac{A}{2} - \frac{2\lambda_m B}{\omega_m} + \frac{Bt}{2} \right] \end{aligned}$$

and:

$$\begin{aligned} \ddot{z}_m(t) &= P_m^* e^{-\lambda_m \omega_m t} \left\{ \left[z_m(t_1) - \frac{B}{2} \right] \cos \omega_{Dm} t \right. \\ &\quad \left. + \left[A - \omega_m^2 z_m(t_1) - \lambda_m \omega_m (z_m(t_1) + \frac{B}{2}) \right] \frac{\sin \omega_{Dm} t}{\omega_{Dm}} \right\}, \\ &\quad + P_m^* \frac{B}{2} \end{aligned}$$

where:

$$A = \ddot{v}_g(t_1)$$

$$B = \frac{\ddot{v}_g(t_2) - \ddot{v}_g(t_1)}{t_2 - t_1}$$

$z_m(t_1), \dot{z}_m(t_1)$ are the initial conditions
for the segment t_1, t_2

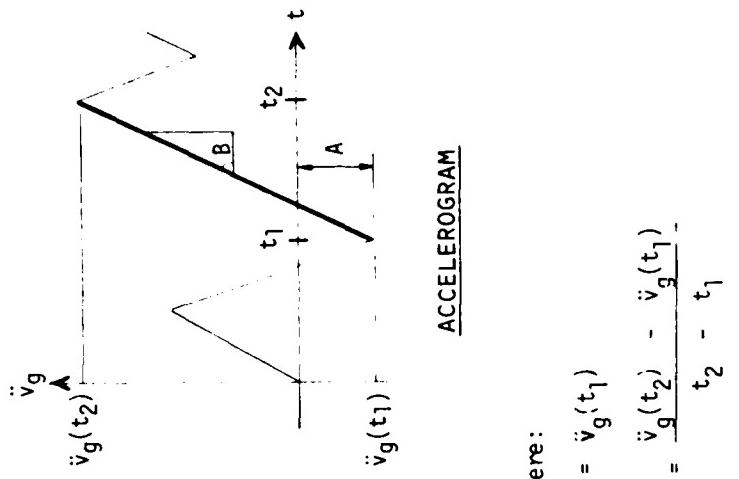


Figure 14. Closed form time integration scheme of CTABS80

E. Response Spectrum Analysis

Unless actual histories of displacements and forces are required for a specific earthquake a more realistic and economical approach for dynamic analysis is via the response spectrum method. For a particular ground motion history $\ddot{v}_g(t)$, the spectrum curve is defined as follows:

The response of a single mass system with damping λ , and circular frequency ω , subjected to a ground motion history $\ddot{v}_g(t)$ is governed by the equation:

$$\ddot{u}(t) + 2\lambda\omega \dot{u}(t) + \omega^2 u(t) = \ddot{v}_g(t)$$

Let u_{max} be the maximum absolute value that $u(t)$ attains. A plot of this maximum displacement versus the frequency ω for each λ is by definition the displacement response spectrum (S_d) for the earthquake $\ddot{v}_g(t)$. A plot of $u_{max}\omega$ is the pseudo-velocity spectrum (PS_v) and a plot of $u_{max}\omega^2$ is the pseudo-acceleration spectrum (PS_a). These pseudo-velocity and acceleration spectra are of the same physical interest but are not an essential part of a response spectrum analysis.

Recalling equation (d), if the dynamic loading on the structure is specified in terms of the pseudo-acceleration spectrum, then the maximum response for the m th mode is given by:

$$z_{m_{max}} = p_m^* \frac{PSa(\omega_m, \lambda_m)}{\omega_m^2}$$

Therefore, the maximum contribution of mode m to the total three dimensional response of the structure is:

$$r_m = Z_{m_{\max}} \phi_m$$

For all modes S_d is, by definition, positive. The maximum modal displacement r_m is proportional to the mode shape ϕ ; and the sign of the proportionality constant is given by the sign of the modal participation factor, P_m^* . Therefore, each maximum modal displacement has a unique sign. Also, the maximum internal modal forces, which are consistently evaluated from the maximum modal displacements, have unique signs.

A complete analysis is performed down to the member force level with the maximum modal displacements of the structure for each individual mode using the backsubstitution procedure described in Chapter II.

The maxima in each mode will generally occur at different times. The combination of the modal components of the displacements and member forces to give resultant values for design purposes is performed at the design parameter level by the following methods.

1. The Square-Root-of-the-Sum-of-the-Squares (SRSS)⁽¹³⁾ method
2. The Absolute Sum (ABS)⁽¹³⁾ method
3. The Complete Quadratic Combination (CQC)⁽¹⁰⁾ method

The SRSS method and the ABS method entirely neglect the signs of the modal contributions. The SRSS method in general gives good approxi-

mations of the dynamic response in structures with well separated frequencies. The ABS method is basically for interest to give an upper bound on the maximum values.

In structures with closely spaced modes or multiple frequencies, the fact that the SRSS method neglects the signs of the modal components may cause the design parameters to be dramatically overestimated in some elements while being significantly underestimated in other elements. The CQC method overcomes this difficulty and it is recommended as the best of the three methods for obtaining the most realistic results.

F. Dynamic Options

The dynamic options currently available in CTABS80 are:

1. Calculation of mode shapes and periods (frequencies)
2. Response spectrum analysis for any acceleration spectrum supplied by the user using the:
 - a. SRSS modal combination as Dynamic load condition I
 - b. Sum of absolute value modal combinations as Dynamic load condition 2
 - c. Complete Quadratic combinations as Dynamic load condition 3
3. Time history analysis maxima for any ground motion supplied by the user as Dynamic load condition 3

Either dynamic analysis condition may be combined with any static load condition.

1. SRSS COMBINATION

$$F = \sqrt{f^T I f} \quad \text{Where } I \text{ is an identity matrix}$$

$(1x1) \quad \sqrt{(1xn) \quad (nxn) \quad (nx1)}$

2. ABS COMBINATION

$$F = f^T \text{ sign } f \quad \text{Where } \text{sign } f \text{ is a unit matrix containing the signs of the corresponding elements of matrix } f$$

$(1x1) \quad (1xn) \quad (nx1)$

3. CQC COMBINATION

$$F = \sqrt{f^T \underline{\zeta} f} \quad \text{Where } \underline{\zeta} \text{ is the matrix of modal cross-correlation coefficients given by:}$$

$(1x1) \quad \sqrt{(1xn) \quad (nxn) \quad (nx1)}$

NOTES/

f = vector of modal components

F = combined resultant

n = number of modes

$$\underline{\zeta}_{ij} = \frac{8\lambda^2(1+r)r^{3/2}}{(1-r^2)^2 + 4\lambda^2r(1+r)^2}$$

where $r = \omega_i/\omega_j$, the ratio of the circular frequencies of the coupling modes and λ is the damping associated with the response spectrum curve being used.

Figure 15. Summary of modal combination techniques used in CTABS80

CHAPTER V: GENERAL OBSERVATIONS

A. Program Application

The effective application of a computer program for the analysis of practical situations involves a considerable amount of experience. The most difficult phase of the analysis is in assembling an appropriate model which captures the major characteristics of the structural behavior of the building. No computer program can replace the engineering judgement of an experienced engineer. It is well said that an incapable engineer cannot do with a ton of computer output what a good engineer can do on the back of an envelope. Correct output interpretation is just as important as the preparation of a good structural model. Verification of unexpected results needs a good understanding of the basic assumptions and the mechanics of the program. Static equilibrium checks are necessary not only to check the computer output but to understand the basic structural behavior of the building.

B. Static Seismic Analysis of Buildings

At the present time, the seismic design of most buildings in California and other earthquake regions of the United States is based upon the Uniform Building Code. The UBC method allows the seismic loads to be approximated by an equivalent set of lateral static loads. The magnitude of the loads is based upon the seismic zone, the structural system, and the fundamental period of the structure. Corrections to compensate for local soil conditions and the physical importance of the structure are also defined.

An approximate formula, specified in the UBC, may be used to estimate the fundamental period. The period associated with the predominant structural mode obtained via the TABS program is more accurate and appropriate. The suggested UBC distribution of the lateral loads over the height of the building is triangular with some correction to allow for higher mode effects. Behavior of structures that have dynamically decoupled regions due to stiffness and/or mass discontinuities, causing significantly non-triangular inertia load patterns are not adequately covered by the code. By examining the structural modes produced by a TABS analysis such structural complexities can be isolated.

The determination of the minimum horizontal torsional design moments, as specified by the UBC for the design of structures having rigid diaphragms, requires the location of a center of rigidity of the structure at each level. The definition of torsional moments on such a basis for multi-story structures is technically vague. It is only meaningful in single story structures where there are no stories above or below to affect the rotation of the level under consideration.

The UBC lateral loads are only a small fraction of the loads developed during a significant earthquake, and must therefore be considered as minimum requirements. As a result of the above mentioned inadequacies the need for a more comprehensive code earthquake analysis methodology is apparent to most structural engineers⁽⁸⁾.

C. Computer Methods Versus Hand Methods

High speed digital computers and the development of computer programs such as TABS have given engineers the capability to consider aspects of

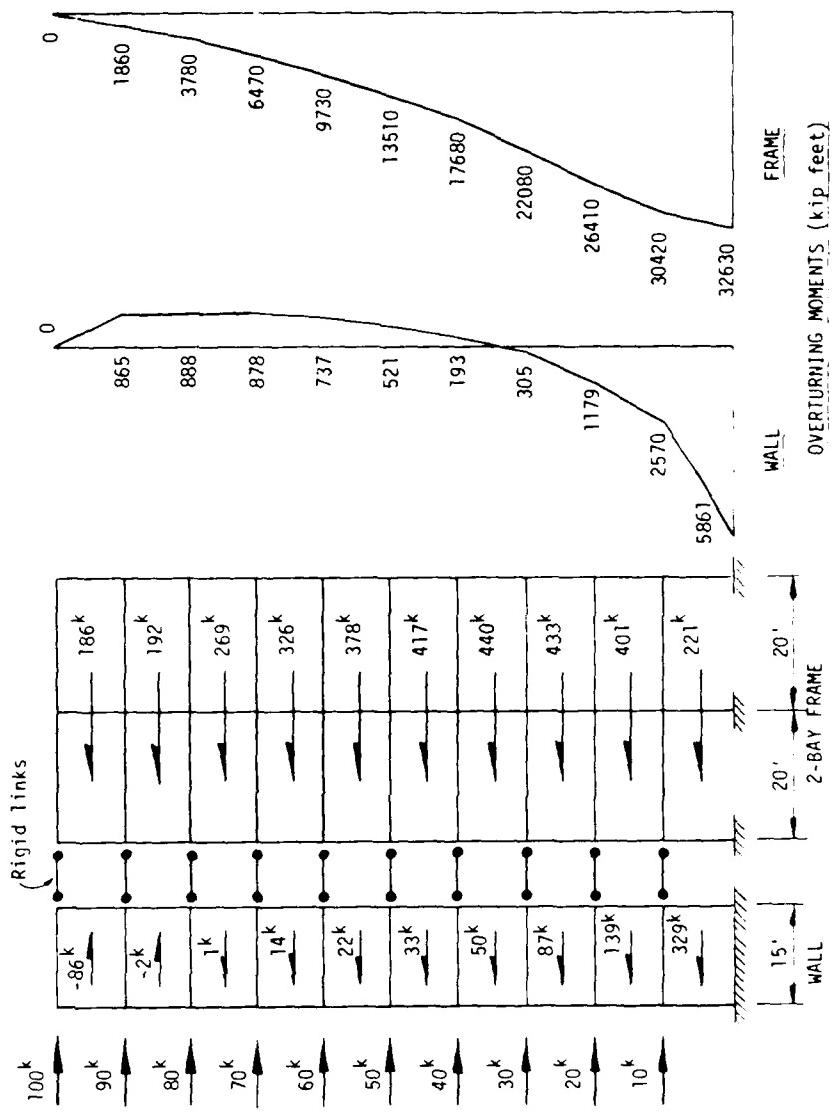
structural behavior that conventional hand analysis techniques have traditionally neglected. Hand analysis techniques used by practicing engineers for the lateral analysis of multistory structures have been shown to violate joint statics and compatibility.

The following examples demonstrate the degree of error that could be present in a conventional hand analysis, by comparison with a TABS analysis; i.e., one that completely satisfies statics, compatibility, and boundary. Examples presented are of simple symmetrical multistory buildings with symmetrical loading. The stories, therefore, translate under lateral load without rotating, thereby keeping the problems clear and demonstrative. The proportions of the structures and magnitudes of the forces have been chosen to generate problems of a nature that a conventional structural engineer is commonly faced with in practice.

(i). Example 1

This is a classic example of shear wall-frame interaction. A 10 story shear wall is connected in parallel with a ten story frame at each story level through a rigid link. The axial deformations in the beams are neglected, thus simulating a rigid diaphragm. Therefore, the lateral displacements of the respective stories of the frame and shear wall are equal. See Figure 16.

Consider the top story. Based on a conventional hand analysis, one would, in general, tend to ignore the stiffness of the frame and conclude that the shear wall takes close to 100% of the applied 100 K, and that the frame being relatively flexible gets a negligible amount of the shear.



NOTE/

Walls are 12" thick
Columns are 24" x 24" typ.
Beams are 12" x 24" typ.
Story height = 10' typ.

Figure 16

A "correct" analysis, however, reveals that the frame has a total shear of 186 K at that level. Thus, the frame, besides carrying the total 100 K applied load, is laterally supporting the shear wall which puts an additional 86 K on the frame. The shear wall is in effect acting as a propped cantilever supported by the frame at the upper story levels.

The phenomenon may be explained as follows: If the frame and shear wall are loaded independently with the load, and the lateral displacements of the respective floors compared, it will be observed that the shear wall has larger lateral displacements in the upper levels, whereas the frame has larger displacements in the lower stories and vice versa. Compatibility of joint rotations will have a significant effect on these displacement patterns. When loaded together, the constraint of equal story displacements is enforced, thus resulting in this unique shear distribution. Notice that in the lower stories the shear gradually shifts to the shear wall.

This example demonstrates the importance of the interaction of all the elements on one another and that the hand analysis method of analyzing an n-story structure as n 1-story structures stacked one over the other with no interaction of one on the other can lead to highly unreliable results.

(ii). Example 2

This problem consists of two 2-story walls and one 1-story wall. See Figure 17a. Again, as in Example 1, the walls are connected by rigid links at the floor levels to simulate a rigid diaphragm and to enforce

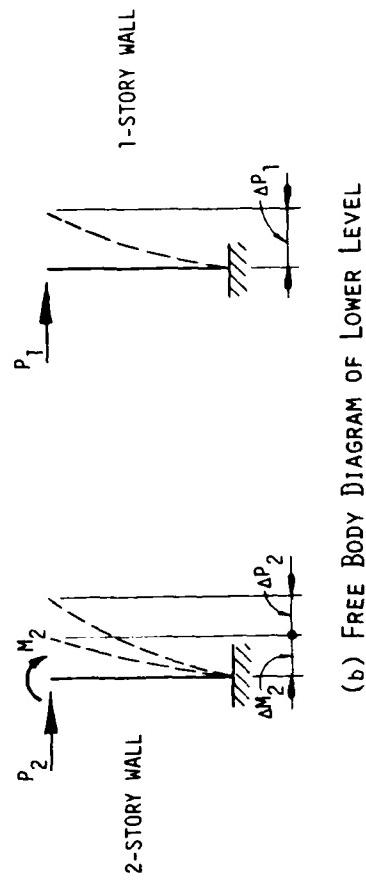
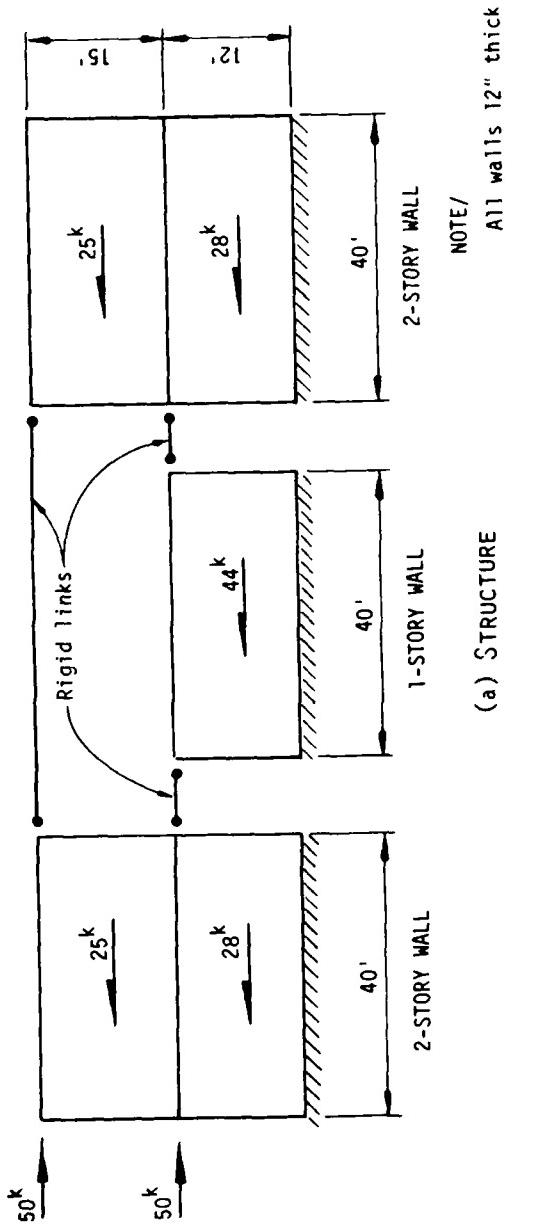


Figure 17

equal lateral story displacements in all the walls. The walls are loaded with a total story load of 50 K at each level. As expected in a conventional hand analysis, the 2-story walls equally share the 50 K lateral load at the upper level.

Now let us consider the shear distribution in the bottom story. The base shear is 100 K. In the light of the fact that there are three resisting elements at this level, all 40' long and 1' thick, a conventional hand analysis would conclude that the base shear will be carried equally by all three elements; that is 33 K each.

A "correct" analysis, however, indicates that the 1-story wall takes over 50% more shear than each 2-story wall. In Figure 17b are presented the free body diagrams of the lower levels of the 1-story wall and the 2-story walls. Consider the lateral story displacements of the 1st level in each wall. In the 1-story wall the lateral displacement, ΔP_1 , is due to P_1 , the shear force in the wall. In the 2-story wall the lateral displacement is due to two factors. Firstly, ΔP_2 , that is due to P_2 , the shear force in the wall and, secondly, ΔM_2 , due to M_2 , the moment at the top of the wall due to the fact that the wall is 2 stories high. Now for the lateral displacements to be equal:

$$\Delta P_1 = \Delta P_2 + \Delta M_2$$

Therefore $\Delta P_1 > \Delta P_2$

so that $P_1 > P_2$

The discrepancy between the conventional hand analysis method and the "correct" method here, again, is due to the fact that the effect of the upper story on the lower story is accounted for incompletely.

(iii). Example 3

This structure consists of 4 walls. Two 4-story walls and two 2-story walls. See Figure 18a. Again, the walls are connected by rigid links at the floor levels to simulate a rigid diaphragm.

In the "correct" analysis the shear forces in the 10 foot walls in the 3rd and 4th levels are as would be expected in a conventional hand analysis. Note the shear distribution at the 2nd level. At this level there is a considerable increase in the story stiffness due to the two 40-foot walls. This restricts the lateral diaphragm movement to the extent that the 10' walls are in effect laterally supported by the diaphragm at this level, and, therefore, behave like over-hanging cantilevers as shown in Figure 18b. This explains why these walls have a negative shear of 154 K each at this level.

The conventional hand analysis method for such problems completely disregards the possibility of negative shear forces occurring in the walls, thereby always assuming that the walls support the diaphragm laterally, and not recognizing that at times the diaphragm may actually be the support for certain walls at certain levels.

(iv). Example 4

This example demonstrates the effect of axial deformations on the distribution of shear to a series of walls. Consider the structure shown in Figures 19a and 19b. The structure consists of two solid walls, and one wall terminating on two columns. In case A, the columns are 12" square, see Figure 19a. Again, the walls are connected by rigid

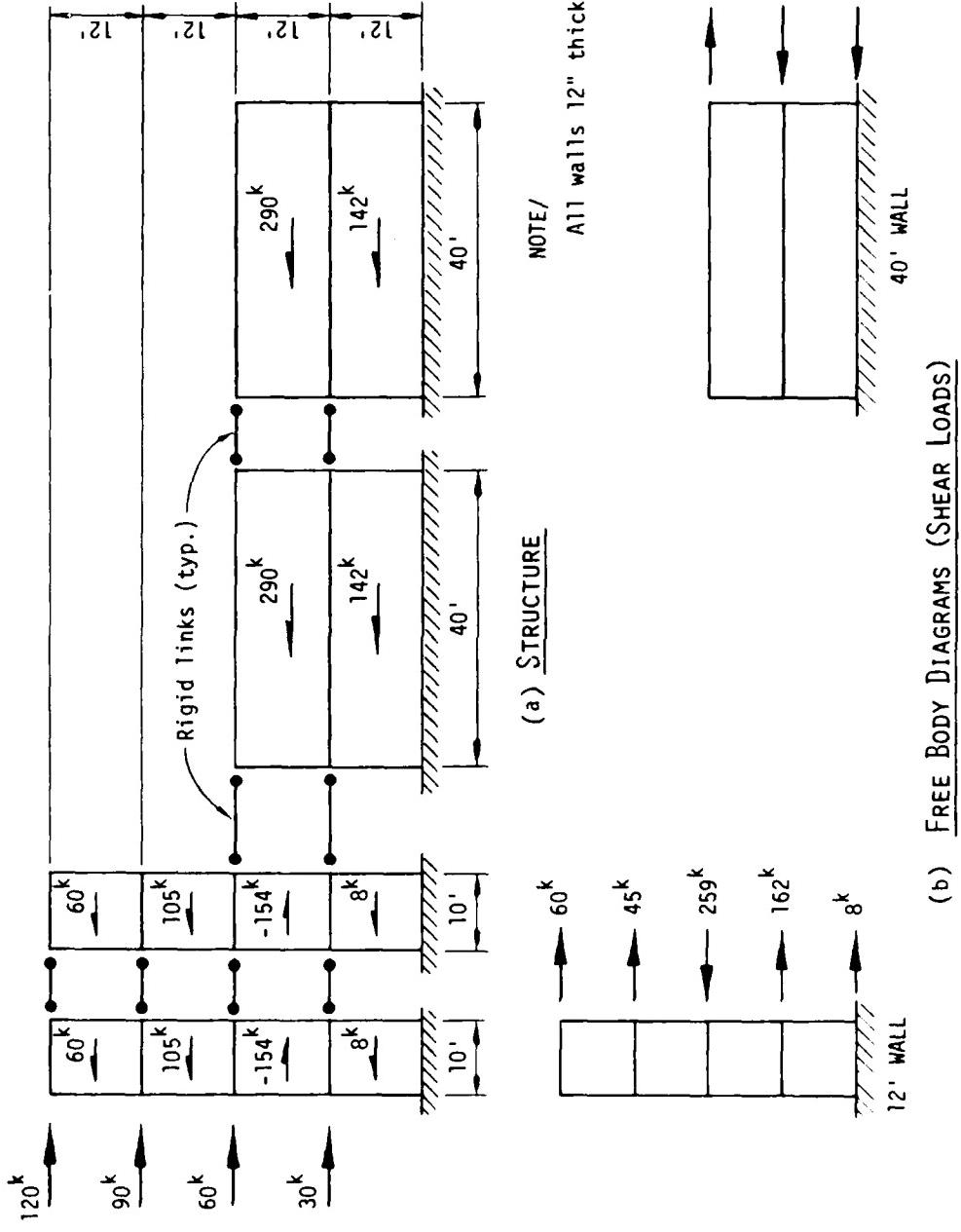


Figure 18

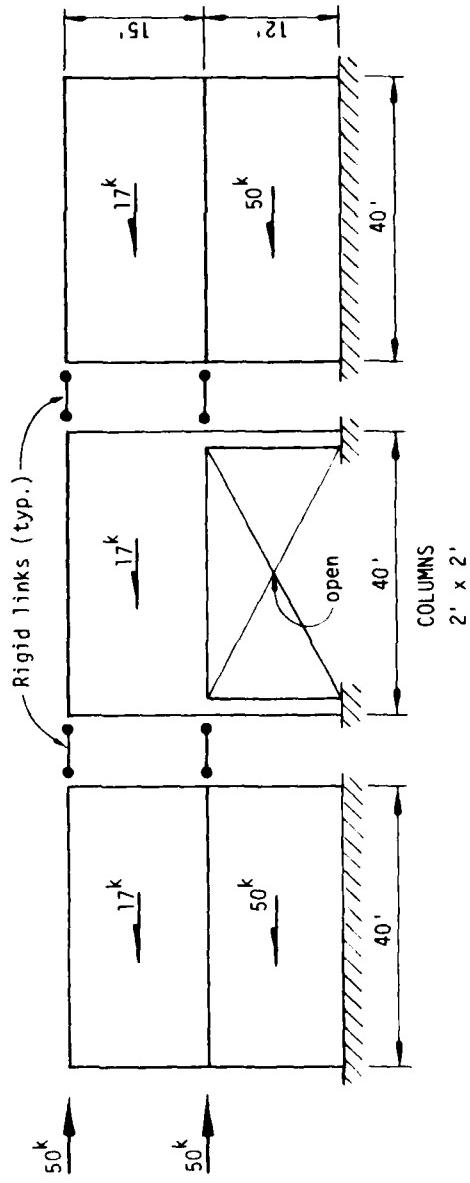


FIGURE 19a: CASE A

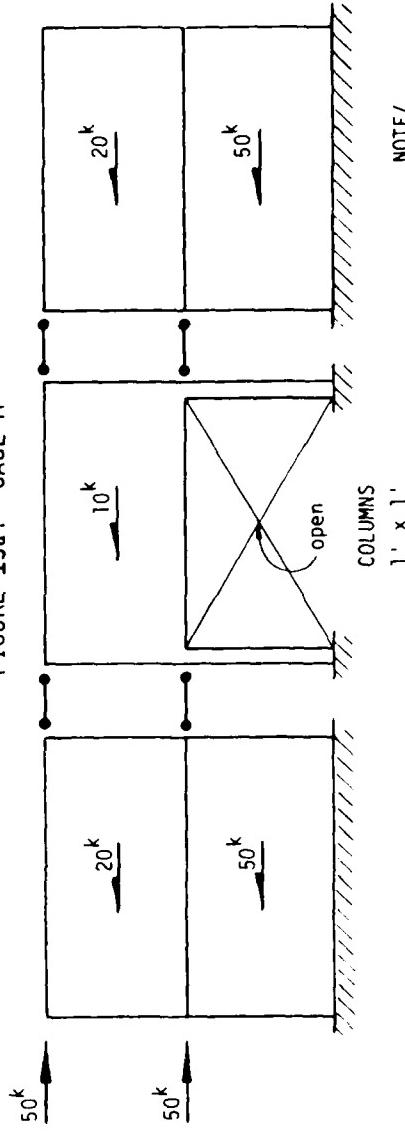


FIGURE 19b: CASE B
Figure 19

links at the story levels.

Consider the shear distribution in the upper level. In case A, a "correct" analysis indicates that the 50 K story shear is distributed approximately equally among the 3 walls. A conventional hand analysis would lead us to the same conclusion. In case B, however, the shear taken by the wall terminating on columns is 50% of that taken by the solid walls. The reason being that the smaller axial area of the columns gives larger axial deformations which, in turn, reduce the lateral rigidity of the wall in the story above.

A conventional hand analysis neglects the effects of axial deformations, and, therefore, would give an equal shear distribution in all three walls regardless of the size of the columns.

(v). Example 5

This example clearly demonstrates the analytical discrepancy in analyzing an n-story structure as n 1-story structures. The structure is a shear wall with the same story height, wall dimensions and openings at every level. See Figure 20.

A conventional hand analysis (analysis of the structure as four 1-story structures) would indicate that the location of the point of contra-flexure of the piers in all the stories would be at a constant distance vertically from the corresponding diaphragm. Also, the ratio of the shear force in pier A to that in pier B in all stories will be constant.

A "correct" solution of the structure, however, shows that there is no point of contra-flexure in pier A in the first three stories. Also, the

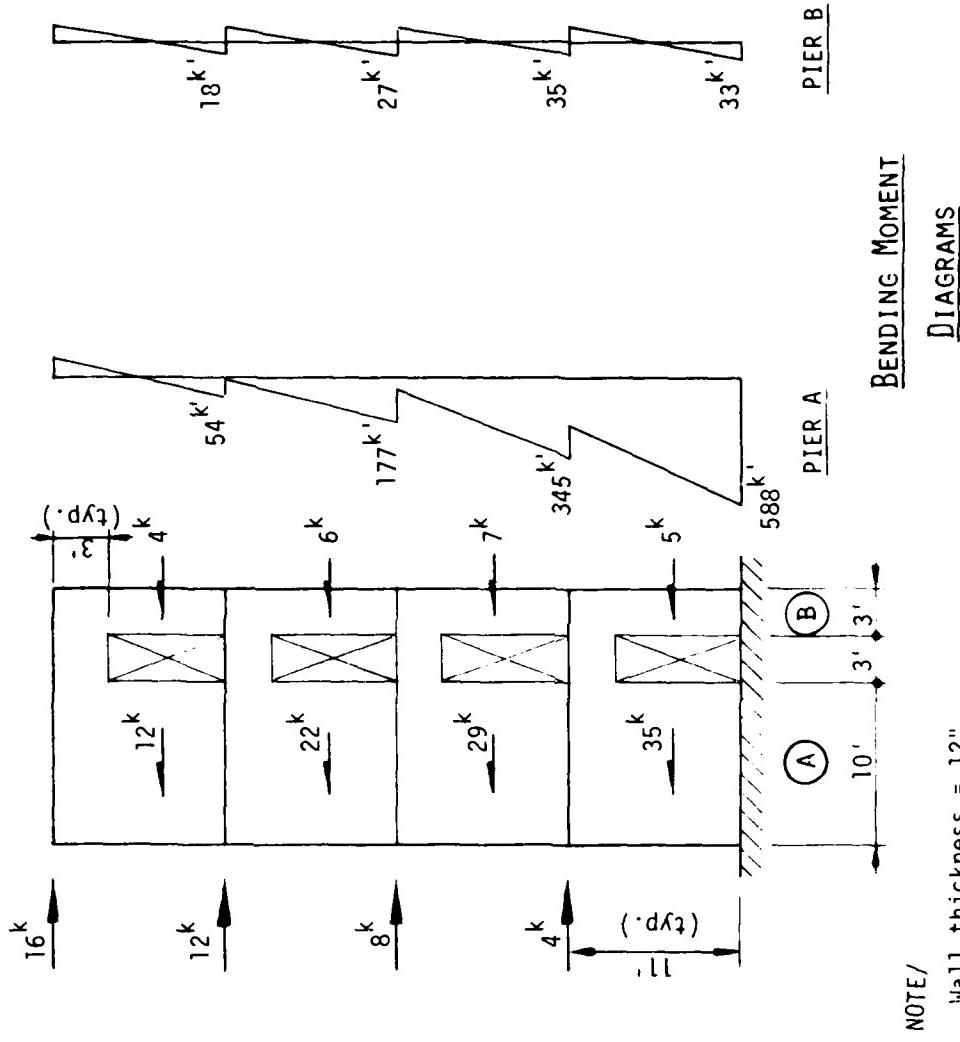


Figure 20

percentage of the story shear carried by pier B is not constant in all stories but decreases as we move into the lower stories.

Joint rotation incompatibility from story to story is the main cause for this discrepancy between the hand analysis and the "correct" analysis.

(vi). Example 6

This is another example demonstrating the effect of axial deformations on the shear distribution. The structure consists of slender piers framing into relatively stiff spandrels and is 8 stories tall. See Figure 21. For all practical purposes, the piers may be considered fixed in rotation at both ends. Since all the piers are of the same size, a conventional hand analysis would indicate that the story shear is distributed equally among the 5 piers.

A "correct" analysis, as we can see, indicates that the piers closer to the center take a higher percentage of the story shear. In the top story for instance, the center pier takes over 65% higher shear than the end pier. This discrepancy is due to the fact that the "correct" analysis considers axial deformations in the piers, whereas the hand analysis does not.

This behavior may be explained by the following analogy. Consider the lateral displacements in a vertical cantilever with a rectangular cross section and lateral loading. If the shear deformations are negligible compared to the bending deformations in the cantilever, the distribution of the shear stress across the section is parabolic with the maximum at the center. However, if the deformation pattern is one of pure shear,

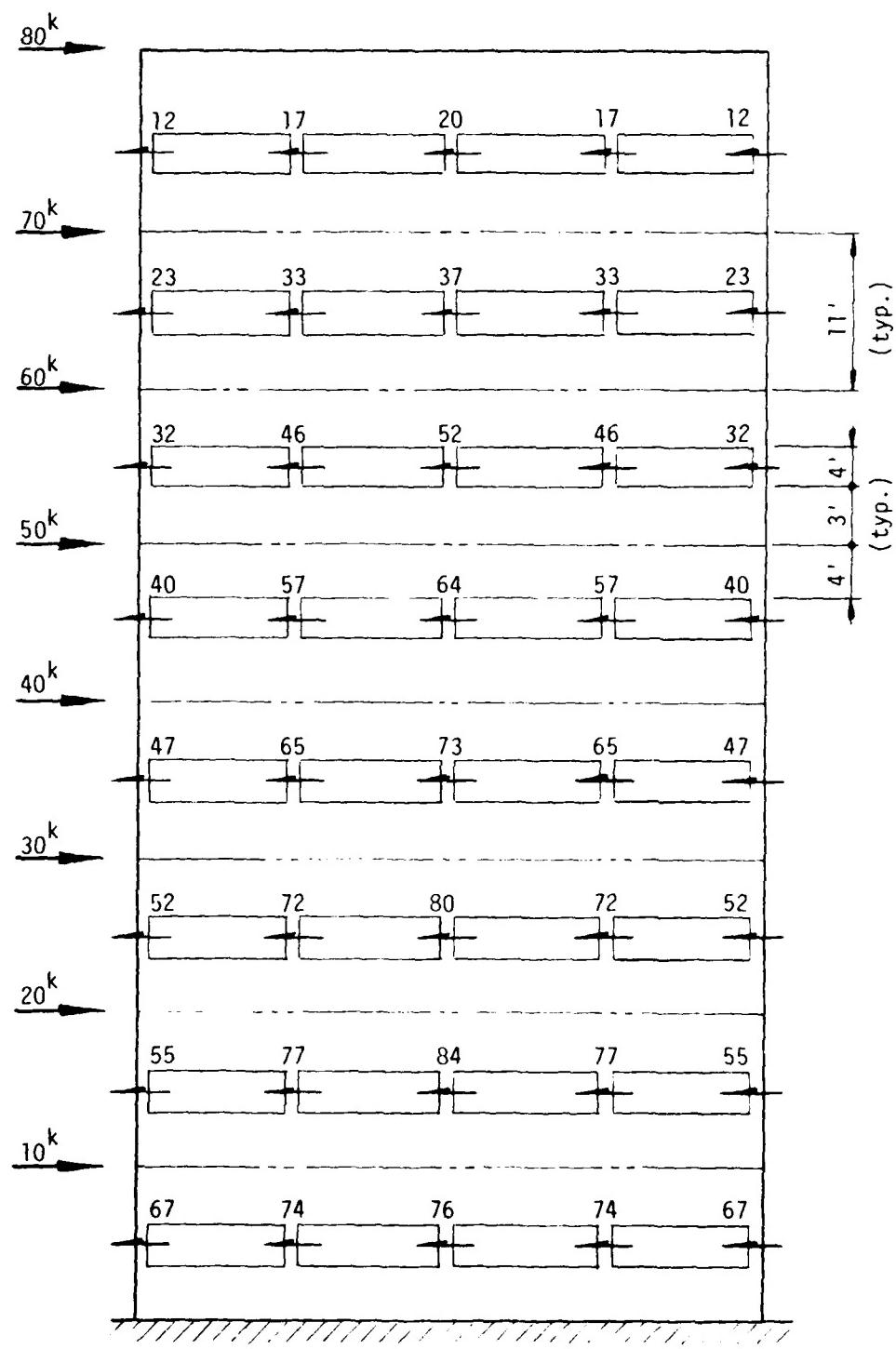


Figure 21

such that the bending deformations are negligible, the shear stress distribution is constant over the section and not parabolic.

The axial deformations of the piers in this example correspond to the bending deformations in the analogy above. If the piers were axially stiff to the extent that there were no axial deformations, the shear distributions in the piers would be equal. However, as the piers deform axially, the piers closer to the middle have heavier shear. This also explains why the shear distribution is more uniform as we move into the lower stories.

D. Dynamic Seismic Analysis of Buildings

The deficiencies of the present seismic design procedures are clearly summarized in Reference 8. It is apparent that the present code is a very approximate method based on the first mode only. The foundation factors discussed later are not considered. Another factor which is important in an elastic analysis is the damping. Spectra for damping of 2 and 10% are shown in Figure 22. It is clear that the Uniform Building Code seismic loads are very small compared to the forces produced in recorded earthquakes. It has been estimated that earthquakes of the Parkfield magnitude can be expected about once per year at some point in California, and earthquakes of the El Centro magnitude may be expected every five or six years.

The selection of a design spectrum for the response spectrum analysis of a particular building will depend on the geographical area, the local soil condition, the type of construction material and the intended use of the

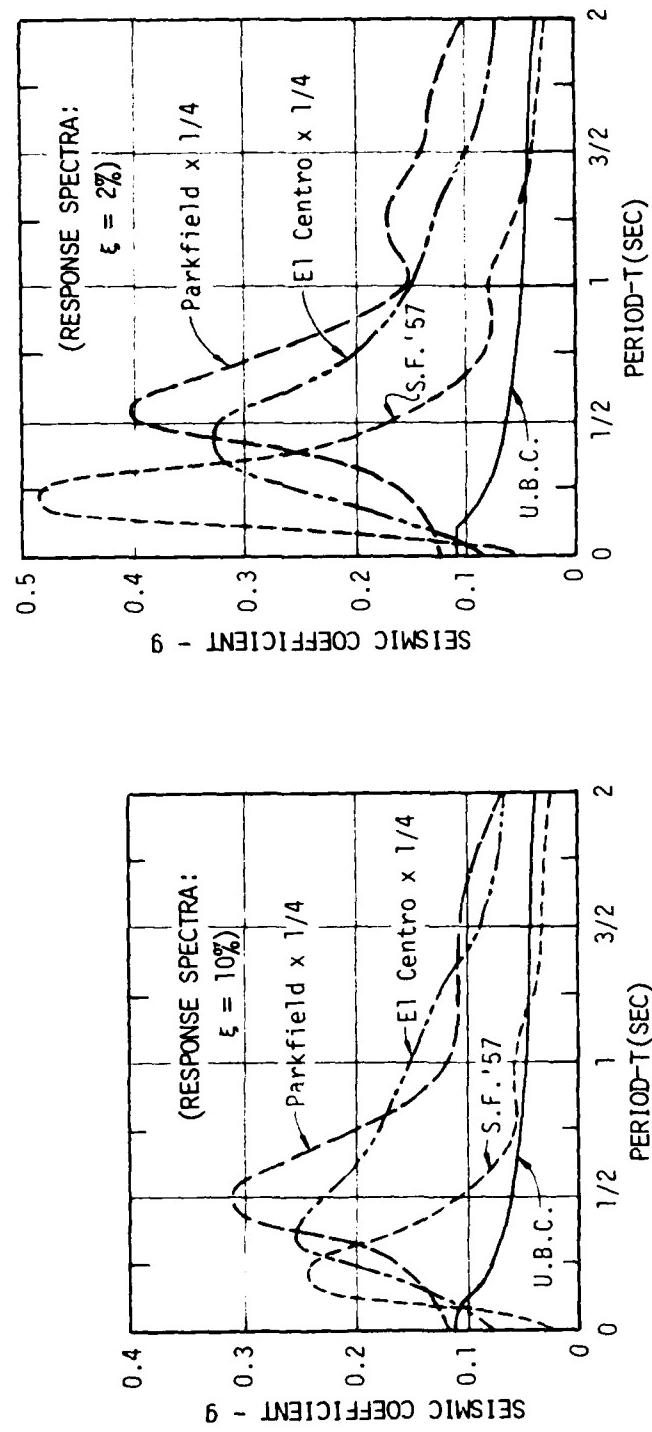


Figure 22. Response spectra

building. Many Soils Engineering firms now specialize in the dynamics of soil systems to evaluate specific sites and recommend shapes and intensities for dynamic response spectra. Most lending agencies are requiring dynamic analysis of structures as part of their financing terms for buildings in major metropolitan areas of California.

For certain types of earthquakes it has been observed that the vertical accelerations are comparable in magnitude to the lateral accelerations. However, all building have been designed elastically for a minimum of 1 g in the vertical direction; therefore, these additional vertical forces very often do not cause direct damage to the structure. Of course, they should be considered in the design of members in addition to the lateral earthquake loads. For most structures the stiffness in the vertical direction is very large; hence, the vertical periods will be very small. Therefore, a dynamic analysis in the vertical direction may not be required. A direct increase in dead load stresses may be a good method to approximate the effects of vertical earthquake loads.

E. Foundation - Building Interaction

Foundation modeling has always been an area of particular concern. The vertical and rotational stiffnesses under each column can be easily input by providing an extra "dummy" story. However, the assigning of accurate stiffness values for these soil springs can be difficult.

In recent years considerable research has been conducted in the area of foundation - building interaction. However, very little of this work has been of direct value to the profession involved in the earthquake analysis

of buildings. Several of the suggested approaches have been difficult to apply in case of complex buildings, or they have had serious theoretical restrictions.

Before foundation interaction effects are included in the analysis it is necessary to define the exact location of the earthquake input. If the design criteria states that the input is at the base of the building then it is impossible to say that the building will modify the input, and it is impossible to include interaction effects.

A large amount of research in this area has been associated with machines vibrating on an infinite foundation where the term radiation damping has been used. This work has little value in earthquake engineering since the energy source is not at the base of the building. It is easy to show that the energy stored in the building is very small compared to the energy stored in the immediate foundation area in the case of earthquake input. Also, the machine vibration problem is a steady state phenomenon, whereas earthquakes produce a transient loading.

The continuous foundation contains an infinite number of degrees of freedom. Therefore, any approach which suggest representing the lateral behavior of the foundation with a simple spring, dashpot and mass system is a very gross approximation. In fact, this technique can produce a filtering effect on the earthquake input and cause serious errors. For lateral earthquake input, this type of approximation is only acceptable in the representation of the rotational stiffness at the base of columns and shear walls.

The most significant factor to consider is the modification of the basic

earthquake rock motion by the layers of soil material under the building⁽⁷⁾.

For certain earthquakes and locations this may be a factor of 2 or 3 in amplification. Therefore, it is very important that the dynamic behavior of the site is studied independently of the building. The results of such a study will result in a suggested acceleration spectrum to be used in the analysis of the building. Figure 23 indicates the type of results which can be expected from such a site analysis.

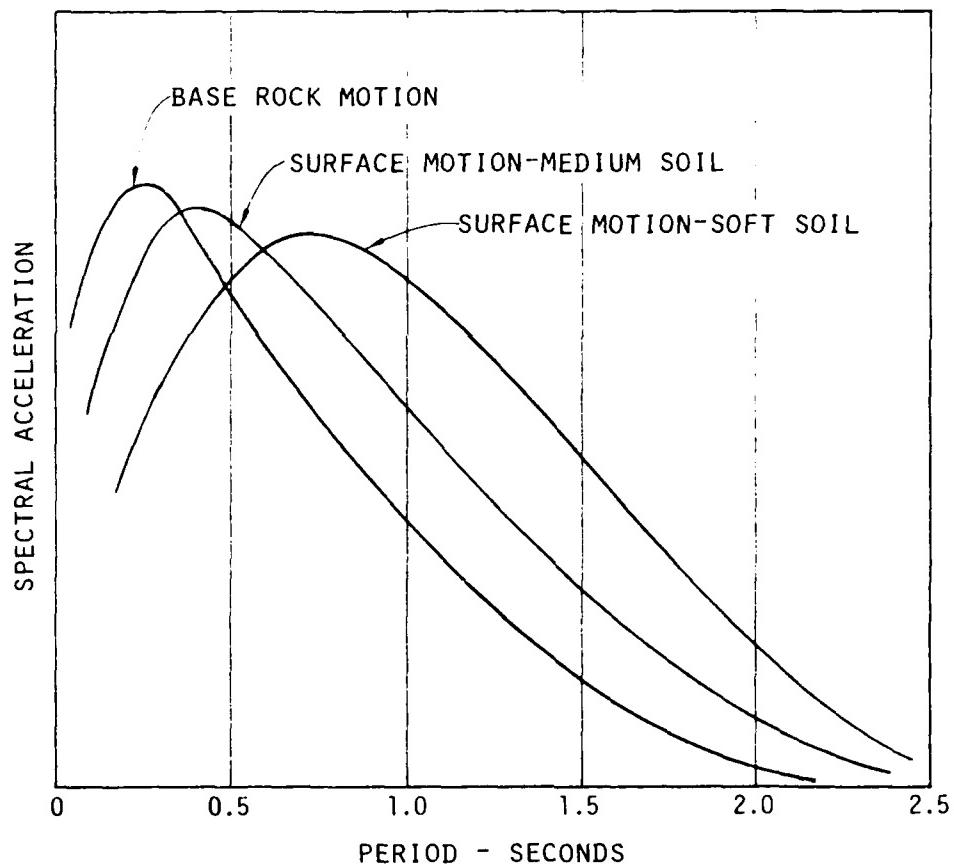


Figure 23. Spectral variation due to soil conditions

CHAPTER VI: INTERNAL ORGANIZATION

An outline of the subroutine structure of CTABS80 is presented in Figure 24. There are seven major calls from CTABS80 associated with the seven major blocks of the program.

1. The first operation is to read the basic control information. The data associated with the complete building (story data and structural lateral loads) is then rolled in via subroutine TABI.
2. The next operation involves reading in the frame data of every different frame in the structure. The frame elevations are plotted, if requested. In non-data check modes the frame stiffnesses are formulated and reduced and the frame lateral stiffness matrices and back-substitution equations are written sequentially on disc. This operation is implemented by the call to subroutine TABF.
3. The call to subroutine TABL reads the frame location data and formulates the complete lateral structural stiffness matrix of the whole building.
4. Subroutine SFRAME causes a plan view of the building to be plotted, showing the frame locations and the directions of their local axes.
5. The call to subroutine TABE gives the modeshapes and frequencies of the structure (TABM) and triggers the automatic UBC lateral seismic load calculation (TUBC). Also the dynamic analysis control information is read in by this call. Structural lateral displacements due to the static loads (TABQ) and response spectrum dynamic loads are obtained at this stage.

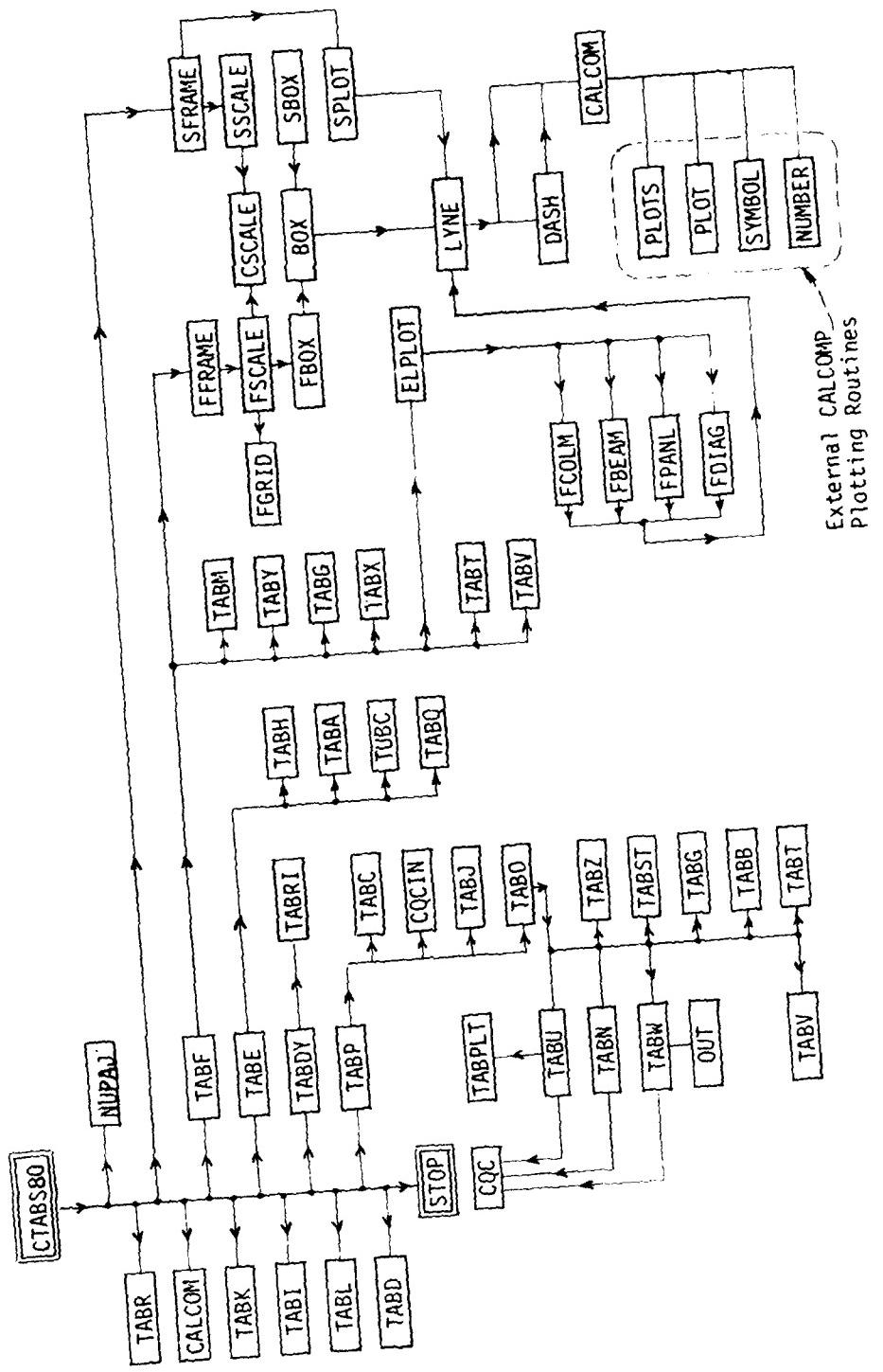


Figure 24. Internal organization of *Cladosau*

6. Subroutine TABDY reads in the time history earthquake ground motion data and causes the structural lateral displacements to be calculated for each time step.
7. Finally, subroutine TABP is called. This subroutine calls TABC to read the load case definition data for each frame. Then TABU is called to print the frame lateral displacements and TABO is called to calculate the frame joint displacements for each static load condition and each spectral mode or response time increment from the back substitution equations previously saved.

As the displacements are calculated the member forces are also evaluated and printed according to the load case definition data (TABW).

CHAPTER VII: CONCLUSIONS

A general computer program for the elastic three-dimensional static and dynamic analysis of frame and shear wall buildings has been presented. For buildings which can be approximated by independent frames and shear walls the program is very economical and easy to use as compared to a general purpose three-dimensional structural analysis program.

Many new options have been implemented in this release to make the program a more practical and useful engineering tool.

The program is based on linear theory. Non-linear behavior such as P-Δ effects and material plasticity are not captured by the program.

If non-linear effects are to be considered a step-by-step response analysis is required; however, this involves a significant increase in computational effort and will be justified for only a limited number of buildings. In addition, the non-linear material properties both for most structural and non-structural members have not been established accurately from experimental work.

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APPENDIX A: FORTRAN IV LISTING OF CTABS80

A1

PROGRAM TAB580 INPUT:OUTPUT:TAPE=INPUT:TAPE=OUTPUT:FILE=
 TAPE1:TAPE2:TAPE3:TAPE4:TAPE5:TAPE6:
 TAPE7:FILE1
DEVELOPED BY
 A GENERAL PROGRAM FOR THE STATIC AND DYNAMIC ANALYSIS OF FRAME
 AND SHEAR WALL THREE-DIMENSIONAL BUILDINGS--- E WILSON AND H DUVY
 8 MARCH 1972---UCB.
RELEASED JUNE 1980
REVISED MARCH 1981
DEVELOPMENT SPONSORED BY
 U. S. ARMY WATERWAYS EXPERIMENT STATION
 VICKSBURG MISSISSIPPI 39181
 Dr. H. BADAK ISHMAN
 DAVID L. REYNOLDS
COMMON /GEOM/ / NS1,NS2,NS3,NS4,NS5,NS6,NS7,NS8,
 COMMON /BLAIS/ / BLAIS1,NS1,NS2,NS3,NS4,NS5,NS6,NS7,NS8
 COMMON /STAB/ / STAB1,NS1,NS2,NS3,NS4,NS5,NS6,NS7,NS8
 COMMON /SIND/ / SIND1,NS1,NS2,NS3,NS4,NS5,NS6,NS7,NS8
 COMMON /IDATA/ / IDATA1,NS1,NS2,NS3,NS4,NS5,NS6,NS7,NS8
 COMMON /FLWA/ / FLWA1,NS1,NS2,NS3,NS4,NS5,NS6,NS7,NS8
 COMMON /PKUP/ / PKUP1,NS1,NS2,NS3,NS4,NS5,NS6,NS7,NS8
 COMMON /PLATE/ / PLATE1,NS1,NS2,NS3,NS4,NS5,NS6,NS7,NS8
 COMMON /ANLY/ / ANLY1,NS1,NS2,NS3,NS4,NS5,NS6,NS7,NS8
 COMMON /AMCS/ / AMCS1,NS1,NS2,NS3,NS4,NS5,NS6,NS7,NS8
DEFINITION OF THE ARMY
 U. S. ARMY WATERWAYS EXPERIMENT STATION
 VICKSBURG MISSISSIPPI 39181
DATA FILE
 TAB580 1 C
 TAB580 2 C
 TAB580 3 C
 TAB580 4 C
 TAB580 5 C
 TAB580 6 C
 TAB580 7 C
 TAB580 8 C
 TAB580 9 C
 TAB580 10 C
 TAB580 11 C
 TAB580 12 C
 TAB580 13 C
 TAB580 14 C
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 TAB580 22 C
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 TAB580 24 C
 TAB580 25 C
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 TAB580 83 C
 TAB580 84 C
 TAB580 85 C
 TAB580 86 C
 TAB580 87 C
 TAB580 88 C
 TAB580 89 C
 TAB580 90 C
 TAB580 91 C
 TAB580 92 C
 TAB580 93 C
 TAB580 94 C
 TAB580 95 C
 TAB580 96 C
 TAB580 97 C
 TAB580 98 C
 TAB580 99 C
 TAB580 100 C

DEFINITION OF THE ARMY
 U. S. ARMY WATERWAYS EXPERIMENT STATION
 VICKSBURG MISSISSIPPI 39181
DATA FILE
 TAB580 1 C
 TAB580 2 C
 TAB580 3 C
 TAB580 4 C
 TAB580 5 C
 TAB580 6 C
 TAB580 7 C
 TAB580 8 C
 TAB580 9 C
 TAB580 10 C
 TAB580 11 C
 TAB580 12 C
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 TAB580 73 C
 TAB580 74 C
 TAB580 75 C
 TAB580 76 C
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 TAB580 91 C
 TAB580 92 C
 TAB580 93 C
 TAB580 94 C
 TAB580 95 C
 TAB580 96 C
 TAB580 97 C
 TAB580 98 C
 TAB580 99 C
 TAB580 100 C

DEFINITION OF THE ARMY
 U. S. ARMY WATERWAYS EXPERIMENT STATION
 VICKSBURG MISSISSIPPI 39181
DATA FILE
 TAB580 1 C
 TAB580 2 C
 TAB580 3 C
 TAB580 4 C
 TAB580 5 C
 TAB580 6 C
 TAB580 7 C
 TAB580 8 C
 TAB580 9 C
 TAB580 10 C
 TAB580 11 C
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 TAB580 94 C
 TAB580 95 C
 TAB580 96 C
 TAB580 97 C
 TAB580 98 C
 TAB580 99 C
 TAB580 100 C

STOP 7777

LSC CONTINUE

CALL SECOND (1111)

SETTING RIGID ZONE REDUCTION FACTOR

RIGID=25

IF INP(0,NF=0) RIGID=0.

IF INP(0,NF=0) RIGID=0.

NINP=1

IF INP(1,0=3) NINP=0

IF INP(1,0=2) NINP=0

IF INP(1,0=1) NINP=0

IF INP(1,0=0) NINP=0

I1=3

I2=3

IFEND .FU.01 GA TU 50

I3=1

IS=MDO-1

>0 MESSAIS13

IF INP(1,0=3) MESSAIS

IF INP(1,0=1) MESSAIS

IF INP(1,0=0) MESSAIS

CALL WUPA 11,27,1155,

WHITE 1001,2001 MSA,MSE,MFO,MSD,MPI,MSP,

MURC,MPS),APL

IF INP(1,0=1) MAF=1

IF INP(1,0=0) MAF=1

REMOVED KTFPS

ADDED KTFPS (INFO, IDATE,

ADDED KTFPS (INFO, IDATE,

STRESS TRANSFORMATION DATA

NEAU: TRIP=100/1 AN=1,AMP

IF LAM(LAM=1,0) AN=1,AMP

IF LAM(LAM=1,0) AN=1,0

IF LAM(LAM=1,0) AN=1,0

ADDED TENTHONAL AN=1,AMP

IF LAM(LAM=1,0) AN=1,0

IF LAM(LAM=1,0) AN=1,0

IF LAM(LAM=1,0) AN=1,0

IF LAM(LAM=1,0) AN=1,0

ADDED TENTHONAL AN=1,AMP

IF LAM(LAM=1,0) AN=1,0

101 TAB580 151
102 TAB580 152
103 TAB580 153
104 TAB580 154
105 TAB580 155
106 TAB580 156
107 TAB580 157
108 TAB580 158
109 TAB580 159
110 TAB580 160
111 TAB580 161
112 TAB580 162
113 TAB580 163
114 TAB580 164
115 TAB580 165
116 TAB580 166
117 TAB580 167
118 TAB580 168
119 TAB580 169
120 TAB580 170
121 TAB580 171
122 TAB580 172
123 TAB580 173
124 TAB580 174
125 TAB580 175
126 TAB580 176
127 TAB580 177
128 TAB580 178
129 TAB580 179
130 TAB580 180
131 TAB580 181
132 TAB580 182
133 TAB580 183
134 TAB580 184
135 TAB580 185
136 TAB580 186
137 TAB580 187
138 TAB580 188
139 TAB580 189
140 TAB580 190
141 TAB580 191
142 TAB580 192
143 TAB580 193
144 TAB580 194
145 TAB580 195
146 TAB580 196
147 TAB580 197
148 TAB580 198
149 TAB580 199
150 TAB580 200


```

SUBROUTINE TABK (KIMP,KINP)
      RENDING $-COMMAND CARDS FROM INPUT STREAM
      COMMON /AUNK/ IDLR,ICARD183
      DATA 1STOP1 /IHT/
      DATA 1STOP2 /ZMMAD/
      DATA LEST /2NS/
      REWIND KIMP
      READ (KIMP,1001) IDLR,ICARD
      IF (IDLR.EQ.1) TEST1 GO TO 10
      IF (IDLR.EQ.2) TEST1,AND (ICARD(1).EQ.1STOP2) GO TO 20
      WRITE (KIMP,10001) IDLR,ICARD
      GO TO 10
    10 IDLR=2H
      DO 30 I=1,19
      IC ICARD(I)=4H
      DO 40 I=1,3
      *C WRITE (KIMP,10001) IDLR,ICARD
      ENDFILE KIMP
      REWIND KIMP
      RETURN
      10:0 FORMAT 1A1,17A4,A6)
      FND

```

```

      SUBROUTINE TABR (KINP,KIMP)
      ERROR MESSAGE SUBROUTINE
      COMMON /GENL/ NS,NOF,NIF,NLD,NAT,NFO,NSD,NOPF
      COMMON /ETRP/ ETREP,ETRD
      COMMON /IMDR/ IMDR,IMDR1,IMDR2,IMDR3,IMDR4,IMDR5
      CALL KUPAJ (1,3,1,TEST1)
      IF (ITAG,F,0,0) GO TO 999
      IF (IMDR,GT,50) GO TO 999
      LERON=1,PERURE=1
      NOPF=1

```

```

      TAB580 393      WRITE (KOUT,10001)
      TAB580 394      C
      TAB580 395      GO TO 11,2,3,*5,6,7,8,9,10,11,12,13,14,15,16,17,18,19,20,21,27.
      TAB580 396      * 23,24,*5,25,26,*27,28,29,30,31,1,ITAG
      TAB580 397      C
      TAB580 398      1 WRITE (KOUT,10011) N
      TAB580 399      GO TU 999
      TAB580 400      C
      TAB580 401      2 WRITE (KOUT,10021) N
      TAB580 402      GO TU 99
      TAB580 403      C
      TAB580 404      3 WRITE (KOUT,10031)
      TAB580 405      GO TU 99
      TAB580 406      C
      TAB580 407      4 WRITE (KOUT,10041)
      TAB580 408      GO TU 99
      TAB580 409      C
      TAB580 410      5 WRITE (KOUT,10051)
      TAB580 411      GO TU 99
      TAB580 412      C
      TAB580 413      6 WRITE (KOUT,10061)
      TAB580 414      LINE=LINE+1
      TAB580 415      GO TU 99
      TAB580 416      C
      TAB580 417      7 WRITE (KOUT,10071)
      TAB580 418      GO TU 99
      TAB580 419      C
      TAB580 420      8 WRITE (KOUT,10081)
      TAB580 421      GO TU 99
      TAB580 422      C
      TAB580 423      9 WRITE (KOUT,10091)
      TAB580 424      LINE=LINE+1
      TAB580 425      GO TU 99
      TAB580 426      C
      TAB580 427      10 WRITE (KOUT,10101)
      TAB580 428      GO TU 99
      TAB580 429      C
      TAB580 430      11 WRITE (KOUT,10111)
      TAB580 431      GO TU 99
      TAB580 432      C
      TAB580 433      12 WRITE (KOUT,10121)
      TAB580 434      GO TU 99
      TAB580 435      C
      TAB580 436      13 WRITE (KOUT,10131)
      TAB580 437      GO TU 99
      TAB580 438      C
      TAB580 439      14 WRITE (KOUT,10141)
      TAB580 440      GO TU 99
      TAB580 441      C
      TAB580 442      15 WRITE (KOUT,10151)
      TAB580 443      N

```

```

      GO TO 99
      1  WRITE (IOUT,1016) N
      16 WRITE (IOUT,1016) N
      GO TO 99
      17 WRITE (IOUT,1017) N
      LINE1,LINE+1
      GO TO 99
      18 WRITE (IOUT,1018) N
      LINE1,LINE+1
      GO TO 99
      19 WRITE (IOUT,1019) N
      LINE1,LINE+1
      GO TO 99
      20 WRITE (IOUT,1020) N
      LINE1,LINE+1
      GO TO 99
      21 WRITE (IOUT,1021) N
      GO TO 99
      22 WRITE (IOUT,1022) N
      GO TO 999
      23 WRITE (IOUT,1023) N
      LINE1,LINE+1
      GO TO 999
      24 WRITE (IOUT,1024) N
      GO TO 999
      25 WRITE (IOUT,1025) N
      CD TO 999
      26 WRITE (IOUT,1026) N
      GO TO 999
      27 WRITE (IOUT,1027) N
      CD TO 999
      28 WRITE (IOUT,1028) N
      GO TO 999
      29 WRITE (IOUT,1029) N
      LINE1,LINE+1
      GO TO 999
      30 WRITE (IOUT,1030)
      TAB580 480   30 WRITE (IOUT,1030)
      TAB580 490   LINE1,LINE+1
      TAB580 491   CD TO 999
      TAB580 492   C
      TAB580 493   31 WRITE (IOUT,1031) N
      TAB580 494   LINE1,LINE+1
      TAB580 495   CD TO 99
      TAB580 496   C
      TAB580 497   C
      TAB580 498   99 WRITE (IOUT,2000)
      TAB580 499   LINE1,LINE+1
      TAB580 500   RETURN
      TAB580 501   C
      TAB580 502   C
      TAB580 503   999 WRITE (IOUT,9999)
      TAB580 504   STOP 12345
      TAB580 505   C
      TAB580 506   C
      TAB580 507   1000 FORMAT (45H0.0 E 0 R 0 * 0
      TAB580 508   1001 FORMAT (45H INCASE BLANK COMMA LENGTH IS STORAGE) N
      TAB580 509   1002 FORMAT (45H STUDY MASS TYPE IS OUT OF RANGE FOR LEVEL
      TAB580 510   1003 FORMAT (45H BEAM PROPERTY TYPE IS OUT OF RANGE OR SEQUENCE
      TAB580 511   1004 FORMAT (45H BEAM PROPERTY TYPE IS NOT OUT OF RANGE OR SEQUENCE
      TAB580 512   1005 FORMAT (45H BEAM LOADING TYPE IS OUT OF RANGE OR SEQUENCE
      TAB580 513   1006 FORMAT (45H NUMBER OF CONCENTRATED LOADS IS OUT OF RANGE/
      TAB580 514   1007 FORMAT (45H BEAM PROPERTY REFERENCE OUT OF RANGE IN BAY
      TAB580 515   1008 FORMAT (45H BEAM LOADING REFERENCE OUT OF RANGE IN BAY
      TAB580 516   1009 FORMAT (45H CONCENTRATED LOADS ARE NOT INPUT IN SEQUENCE/
      TAB580 517   1010 FORMATTED NUMBER IS NOT EQUAL TO RIGID LINE NUMBER
      TAB580 518   1011 FORMATTED COLUMN NUMBER IS NOT EQUAL TO RIGID LINE NUMBER
      TAB580 519   1012 FORMATTED PANEL NUMBER IS NOT EQUAL TO RIGID LINE NUMBER
      TAB580 520   1013 FORMATTED PANEL NUMBER IS NOT EQUAL TO RIGID LINE NUMBER
      TAB580 521   1014 FORMATTED DIAGONAL LEVEL NUMBER OUT OF RANGE IN DIAC
      TAB580 522   1015 FORMATTED DIAGONAL COLUMN NUMBER OUT OF RANGE IN DIAC
      TAB580 523   1016 FORMATTED DIAGONAL COLUMN HEIGHT IS NOT GREATER THAN IFPO/
      TAB580 524   1017 FORMATTED CLEAR COLUMN HEIGHT IS NOT GREATER THAN IFPO/
      TAB580 525   1018 FORMATTED CLEAR BEAM LENGTH IS NOT GREATER THAN ZERO /
      TAB580 526   1019 FORMAT (45H STARTING BAY NUMBER IS GREATER THAN ENDING BAY NUMBER/TAB580 526C
      TAB580 527   1020 FORMAT (45H UPPER COLUMN/ TAB580 528
      TAB580 529   1021 FORMAT (45H COMPLETED LOAD LIES UN RIGID LINE IN BAY
      TAB580 530   1022 FORMAT (45H TRAPEZOIDAL LOAD NUMBER IS OUT OF SEQUENCE/RANGE
      TAB580 531   1023 FORMAT (45H TRAPEZOIDAL LOAD NUMBER IS IDENTICAL/
      TAB580 532   30M COORDINATES FOR FEAK NUMBER 101
      TAB580 533   1024 FORMAT (45H MASS NOT GREATER THAN ZERO AT LEVEL
      TAB580 534   1025
      TAB580 535   1026
      TAB580 536   1027
      TAB580 537   1028
      TAB580 538   1029
      TAB580 539   1030
      TAB580 540   1031
      TAB580 541   1032
      TAB580 542   1033
      TAB580 543   1034
      TAB580 544   1035
      TAB580 545   1036
      TAB580 546   1037
      TAB580 547   1038
      TAB580 548   1039
      TAB580 549   1040
      TAB580 550   1041
      TAB580 551   1042
      TAB580 552   1043
      TAB580 553   1044
      TAB580 554   1045
      TAB580 555   1046
      TAB580 556   1047
      TAB580 557   1048
      TAB580 558   1049
      TAB580 559   1050
      TAB580 560   1051
      TAB580 561   1052
      TAB580 562   1053
      TAB580 563   1054
      TAB580 564   1055
      TAB580 565   1056
      TAB580 566   1057
      TAB580 567   1058
      TAB580 568   1059
      TAB580 569   1060
      TAB580 570   1061
      TAB580 571   1062
      TAB580 572   1063
      TAB580 573   1064
      TAB580 574   1065
      TAB580 575   1066
      TAB580 576   1067
      TAB580 577   1068
      TAB580 578   1069
      TAB580 579   1070
      TAB580 580   1071
      TAB580 581   1072
      TAB580 582   1073
      TAB580 583   1074
      TAB580 584   1075
      TAB580 585   1076
      TAB580 586   1077
      TAB580 587   1078
      TAB580 588   1079
      TAB580 589   1080
      TAB580 590   1081
      TAB580 591   1082
      TAB580 592   1083
      TAB580 593   1084
      TAB580 594   1085
      TAB580 595   1086
      TAB580 596   1087
      TAB580 597   1088
      TAB580 598   1089
      TAB580 599   1090
      TAB580 600   1091
      TAB580 601   1092
      TAB580 602   1093
      TAB580 603   1094
      TAB580 604   1095
      TAB580 605   1096
      TAB580 606   1097
      TAB580 607   1098
      TAB580 608   1099
      TAB580 609   1100
      TAB580 610   1101
      TAB580 611   1102
      TAB580 612   1103
      TAB580 613   1104
      TAB580 614   1105
      TAB580 615   1106
      TAB580 616   1107
      TAB580 617   1108
      TAB580 618   1109
      TAB580 619   1110
      TAB580 620   1111
      TAB580 621   1112
      TAB580 622   1113
      TAB580 623   1114
      TAB580 624   1115
      TAB580 625   1116
      TAB580 626   1117
      TAB580 627   1118
      TAB580 628   1119
      TAB580 629   1120
      TAB580 630   1121
      TAB580 631   1122
      TAB580 632   1123
      TAB580 633   1124
      TAB580 634   1125
      TAB580 635   1126
      TAB580 636   1127
      TAB580 637   1128
      TAB580 638   1129
      TAB580 639   1130
      TAB580 640   1131
      TAB580 641   1132
      TAB580 642   1133
      TAB580 643   1134
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      TAB580 680   1171
      TAB580 681   1172
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      TAB580 686   1177
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      TAB580 698   1189
      TAB580 699   1190
      TAB580 700   1191
      TAB580 701   1192
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      TAB580 703   1194
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      TAB580 705   1196
      TAB580 706   1197
      TAB580 707   1198
      TAB580 708   1199
      TAB580 709   1200
      TAB580 710   1201
      TAB580 711   1202
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      TAB580 743   1234
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      TAB580 750   1241
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      TAB580 768   1259
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      TAB580 809   1300
      TAB580 810   1301
      TAB580 811   1302
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      TAB580 850   1341
      TAB580 851   1342
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      TAB580 856   1347
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      TAB580 888   1379
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      TAB580 899   1390
      TAB580 900   1391
      TAB580 901   1392
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      TAB580 950   1441
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      TAB580 978   1469
      TAB580 979   1470
      TAB580 980   1471
      TAB580 981   1472
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      TAB580 999   1490
      TAB580 1000   1491
      TAB580 1001   1492
      TAB580 1002   1493
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      TAB580 1004   1495
      TAB580 1005   1496
      TAB580 1006   1497
      TAB580 1007   1498
      TAB580 1008   1499
      TAB580 1009   1500
      TAB580 1010   1501
      TAB580 1011   1502
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      TAB580 1100   1591
      TAB580 1101   1592
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      TAB580 1106   1597
      TAB580 1107   1598
      TAB580 1108   1599
      TAB580 1109   1600
      TAB580 1110   1601
      TAB580 1111   1602
      TAB580 1112   1603
      TAB580 1113   1604
      TAB580 1114   1605
      TAB580 1115   1606
      TAB580 1116   1607
      TAB580 1117   1608
      TAB580 1118   1609
      TAB580 1119   1610
      TAB580 1120   1611
      TAB580 1121   1612
      TAB580 1122   1613
      TAB580 1123   1614
      TAB580 1124   1615
      TAB580 1125   1616
      TAB580 1126   1617
      TAB580 1127   1618
      TAB580 1128   1619
      TAB580 1129   1620
      TAB580 1130   1621
      TAB580 1131   1
```



```

420 D-CPI5,MC)ORIGID
IF (IXL-A-BALF,-.01 CALL TABB 1M,17)
(
  IF (IPLT-.0,01 GO TO 940
  Y=0,
  IF (N-.MC) Y=Y+1
  JD15=MC
  IF (JD15=.MC) JD15=0
  CALL EXPLOD (EXML,BAL,TML),DD,CPI5,MC),CPI5,MC)+.0D,IP1,1.1
  %C CONTINUE
(
  IF (INP1,.0,01 GO TO 940
  A4=0
  B=0
  IF (A4,L1,0,01 B=0.0
  IF (A4,L1,0,01 A=0.0
  X1=X1-.4M
  BH=0.0
  IF (CPI5,MC) 1.40+.30-.425
  A25 98=1.40+.30-.425
  A10 COMMA2,-ACPI1,MC/CPI1,-ACPI2/CPI1,-ACPI3/CPI1,-ACPI4,MC)1
  S=ACOMMA2,-.4M
  SB=COMPMET,-.8M
  SC=CPI42,MC/CPI1,-CPI2/RL
  CALL TABY5A5,SC,RL,A,0)
  LNL31=20P
  LNL31=LNL31+AN
  LNL61=LNL61-1
  LNL61=LNL61-1
  LNL61=ANM
  LNL71=LNL71+1
  CALL TABT11,1.1,P,4M)
  %C CONTINUE
  P1M,17,0.0
  2. READ READ PARTCLS
  IF (TABB,.0,01 GO TO 945
  N=4
  DO 400 P=1,N
  M=1
  IF (P=1,M=1)
  M=ACPI1,MC
  ACPI1,MC
  B=CPI1,MC/2.
  B=CPI1,MC/2.

```

A15

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TAB50 1201 IF (IPLT,.0,01 GO TO 940
TAB50 1202 IF (M-.0,1) DD13=1-8
TAB50 1203 IF (M-.0,MC) DD13=0
DD13=0
TAB50 1205 DD13=A
TAB50 1206 IF (M,CO,11) GO TO 605
TAB50 1207 MC=LICH-.4M
TAB50 1208 MC=LICH-.4M
TAB50 1209 DD13=CPIS,MC/L1/2.
TAB50 1210 DD13=CPIS,MC/2.
TAB50 1211 605 COMINUE
TAB50 1212 1450 1272 1450 1272
TAB50 1213 535 00,55,LC,MLD
TAB50 1214 2011=UNM(M,1)
TAB50 1215 2015=EFF
TAB50 1216 2016=BN
TAB50 1217 IF (JD16,.0,MC) JD16=0
TAB50 1218 CALL EXPLOD (EXML,XML,TML),DD,BP15,MB),BP16,MB),BP17,MB),BP18,MB)
TAB50 1219 960 CONTINUE
TAB50 1220 C
TAB50 1230 1300 1300 1300
TAB50 1301 1301 1301 1301
TAB50 1302 1302 1302 1302
TAB50 1303 1303 1303 1303
TAB50 1304 1304 1304 1304
TAB50 1305 1305 1305 1305
TAB50 1306 1306 1306 1306
TAB50 1307 1307 1307 1307
TAB50 1308 1308 1308 1308
TAB50 1309 1309 1309 1309
TAB50 1310 1310 1310 1310
TAB50 1311 1311 1311 1311
TAB50 1312 1312 1312 1312
TAB50 1313 1313 1313 1313
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TAB50 1316 1316 1316 1316
TAB50 1317 1317 1317 1317
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TAB50 1320 1320 1320 1320
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TAB50 1322 1322 1322 1322
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TAB50 1324 1324 1324 1324
TAB50 1325 1325 1325 1325
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TAB50 1330 1330 1330 1330
TAB50 1331 1331 1331 1331
TAB50 1332 1332 1332 1332
TAB50 1333 1333 1333 1333
TAB50 1334 1334 1334 1334
TAB50 1335 1335 1335 1335
TAB50 1336 1336 1336 1336
TAB50 1337 1337 1337 1337
TAB50 1338 1338 1338 1338
TAB50 1339 1339 1339 1339
TAB50 1340 1340 1340 1340
TAB50 1341 1341 1341 1341
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TAB50 1344 1344 1344 1344
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TAB50 1355 1355 1355 1355
TAB50 1356 1356 1356 1356
TAB50 1357 1357 1357 1357
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TAB50 1359 1359 1359 1359
TAB50 1360 1360 1360 1360
TAB50 1361 1361 1361 1361
TAB50 1362 1362 1362 1362
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TAB50 1364 1364 1364 1364
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TAB50 1377 1377 1377 1377
TAB50 1378 1378 1378 1378
TAB50 1379 1379 1379 1379
TAB50 1380 1380 1380 1380

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415 IF (MPLT.FQ.01 CD 10 570
CALL TAB155,SP,M4,I
416 IF (INMPFQ.01 CD 10 600
M1,NS1,NN1,SP1
CALL TAB155,CD 10 571
IF (TEST1,SP,10 620
WRITE (UNIT=8000) 10 620
LINE-1,NE-6
417 WRITE (UNIT=9000) 901NL+13,VER1
901 CONTINUE

        DRIFT LATERAL STEIFFNESS ON TAPF
418 WRITE(1,5)
5 IF (PLTFQ.01 CD 10 940
PLOTTING SILL HEIGHTS
419 IF (INMPFQ.01 CD 10 555
DO 110 10
110 DO 111 10
111 DO 112 10
112 DO 113 10
113 DO 114 10
114 CALL ELEM1 (A1H,A2H,A3H,A4H),0.0,DD,SL (H1H),SL (H2H),JD,PLTFQ
1151 CONTINUE
1155 CALL FF SHAPE INSL1,0,KEY,0D,NS1,M5,M6,1F,21
940 CONTINUE

        IF (MPLT.FQ.01 CD 10 939
CALL TAB155,SP,M4,I
941 WRITE (31,M4,CP,BP,EEF,LD,LDA,ICLP,SEFF,PP,PDIC,PDIG,1
M4FF,13) IF,MC,AS,ACP,NMF,NFF,MAPN,NDIC,MC,ONE
942 RETURN

1000 FORMAT (17F10.01
2000 10B4I11HMMSS/17F11.21)
1000 10B4I11HMMSS/17W SILL DEPTHS/17F11.21)
1111 10B4I11HMMSS/17W SILL DEPTHS/17F11.21)
1155 10B4I11HMMSS/17W SILL DEPTHS/17F11.21)
1156 10B4I11HMMSS/17W SILL DEPTHS/17F11.21)

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AD-A107 635

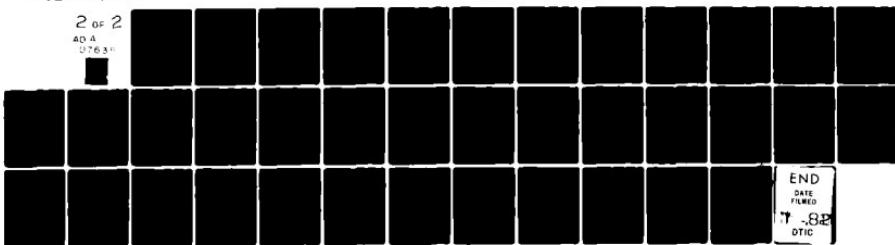
COMPUTERS/STRUCTURES INTERNATIONAL OAKLAND CA
THEORETICAL BASIS FOR CTABS80: A COMPUTER PROGRAM FOR THREE-DIM--ETC(U)
SEP 81 E L WILSON, H H DOVEY, A HABIBULLAH
WES-TR-K-B1-2

F/G 13/13

NL

UNCLASSIFIED

2 OF 2
AD A
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END
DATE
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00 00 100 J1,N
A1,J1,J1,J1-A1,A1,A1,J1
100 A1,J1,J1-A1,J1,J1
DO 110 L1,N
110 01,J1,J1,J1-A1,J1,J1
120 CONTINUE
GO TO 50
C   BACK SUBSTITUTION
C
130 N=N-1
IF IP.EQ.0 GO TO 150
N=N+1
DO 140 L1,N
140 R1,NL-BNL-L1,N,J1,N,J1,L1
GO TO 150
C
150 RETURN
END
C
SUBROUTINE TANL(MSS,MR,SD,AMSS,AMRF,ME1)
C   ASSEMBLING LATERAL STIFFNESS
C
DIMENSION SSEN1,RF1,BRNS,OB,AMST1,S1,RF1,ME1
COMMON /CEN1/ MAT,ODE,MFL,MLD,MLN,INFO,MDP,MDC,MDC,
COMMON /CEM2/ MCTMSS,1,1,15
COMMON /FEM2/ BLAB11,AN1,OMP1,O
COMMON /FEMC/ IMLN2B1,DATE21,MPGE21,MLN1,MLN1
COMMON /STATF/ R1P,K1,K1,ACOT1,STR,TAPE
COMMON /ADPT/ N1P,ADP1
COMMON /JUNK1/ J1,N,J1,J1
C
IF (INOPT.EQ.1) GO TO 105
REWIND 7
DO 50 I=1, MSS
  DO 40 J=1,4
    40 R11,J1=0
    DO 50 J=1,MSS
      50 S11,J1=0
      IF (IN50,MF.0) GO TO 60
TAB580 1957      IF (IN50,MF.0) GO TO 60
TAB580 1958      S511,J1=2,I1,I2,I3,I4,I5
TAB580 1959      S511,J1=1,I1,I2,I3,I4,I5
TAB580 1960      60 00 100 J1,J1,J1
TAB580 1961      00 100 J1,J1,J1
TAB580 1962      LL55,J1,J1,J1,J1,J1,J1
TAB580 1963      100 R11,J1,J1,J1,J1,J1,J1
TAB580 1964      C
TAB580 1965      105 IF (IN1P.EQ.0) GO TO 110
TAB580 1966      LINE=19
TAB580 1967      CALL MUPAJ 11,7,TEST1
TAB580 1968      WRITE (OUT1,3000)
TAB580 1969      110 IFP=0
TAB580 1970      C
TAB580 1971      REWIND 1
TAB580 1972      C
TAB580 1973      00 500 R11,MIF
TAB580 1974      READ (INP1,1000) IF1,F1,X1,Y1,Z1,T1,MD1,I1,J1=1,4
TAB580 1975      IF (IN1P.EQ.0) GO TO 110
TAB580 1976      CALL MUPAJ 11,1,TEST1
IF (TEST1.LO.O) GO TO 100
WRITE (OUT1,3000)
LINE=19
TAB580 1977      100 WRITE (OUT1,2001) R11,MIF,IFCA1,X1,Y1,X2,Y2,MD1K,J1,J2
TAB580 1978      17C IF(I1.EQ.1)PP1 GO TO 150
TAB580 1979      IF (I1.EQ.2)PP1 CALL TABR 16,22
TAB580 1980      IF (I1.EQ.3)PP1 CALL TABR 16,22
TAB580 1981      IF (INOPT.ME.1)
TAB580 1982      READ (21,LDU,MT15111,1=1,LDU),TIR11111,1=1,MT11111,1=1,4
TAB580 1983      IFP=IF
TAB580 1984      150 YY11112
TAB580 1985      MLN2B1,DATE21,MPGE21,MLN1,MLN1
TAB580 1986      IF (I1,I2,I3,I4,I5) CALL TABR 16,22
TAB580 1987      IF (INOPT.EQ.1) GO TO 100
DO 200 MNY,M1
 200 MNY,M1
  MLEN2B1,1,1
TAB580 1988      IMLN2B1,1,1
TAB580 1989      IMLN2B1,1,1
TAB580 1990      IMLN2B1,1,1
TAB580 1991      200 D1,N1,K1,AN1,MLN1,MLN1
TAB580 1992      C
TAB580 1993      4111,J1=1,I2,I3,I4,I5
TAB580 1994      A112,I1=1,I2,I3,I4,I5
TAB580 1995      A112,I1=1,I2,I3,I4,I5
TAB580 1996      A112,I1=1,I2,I3,I4,I5
TAB580 1997      C
TAB580 1998      KRD
TAB580 1999      DU 400 MNY,M1,MT1
TAB580 2000      A131P=0,IN1,M1
TAB580 2001      MLN2B1,1,1
TAB580 2002      MNY,MLN1,1,1
TAB580 2092      C

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1003 FORMAT (BHOTIME... 1014,F7.3)
1005 FORMAT (I1)
2000 FORMAT (13H DISPLACEMENTS ALL ZERO.. NOT PLOTTED )
2001 FORMAT (14G SCALE - ONE INCH = 15.69 X106MMAXUM AT T=)
1 SIMONOTE - PLOT IS OF DYNAMIC DISPLACEMENTS ONLY AND DOES NOT /
2 7X, AND INCLUDE ANY SCALING BY LOAD CASE DEFINITION CARDS
FNO

SUBROUTINE TABP (INOT)
C CALCULATING MEMBER FORCES AND STRESSES
C
COMPAR /GENL / NSI,MDF,NFE,NLD,NAT,NFO,NSD,NDF,I,MRC,D,NDSP,NUSC,
COPRDN /STAPE,ATMP,INP,KOUT,KSTR,TAPE,TAPE
COPRDN /KOUT / NIP,NOUT
COPRDN /JUNK / FRED44,IF,IFC
COPRDN /DYN / NTYPE,DT,NPC,DAMP,NHD,1M1YP,MDT
COPRDN ALL
C
IF (NAT,ME,3) P=0
NOD
LDMO,MSI,NDF
L1L0,2PMST
L2L1P
L3L2P
L4L3L4L0
L5L6L7L0
L8L9L10
L11L12L0
L13L14L0
L15L16L0
L17L18L0
L19L20L0
L21L22L0
L23L24L0
L25L26L0
L27L28L0
L29L30L0
L31L32L0
L33L34L0
L35L36L0
L37L38L0
L39L40L0
L41L42L0
L43L44L0
L45L46L0
L47L48L0
L49L50L0
L51L52L0
L53L54L0
L55L56L0
L57L58L0
L59L60L0
L61L62L0
L63L64L0
L65L66L0
L67L68L0
L69L70L0
L71L72L0
L73L74L0
L75L76L0
L77L78L0
L79L80L0
L81L82L0
L83L84L0
L85L86L0
L87L88L0
L89L90L0
L91L92L0
L93L94L0
L95L96L0
L97L98L0
L99L100L0
L101L102L0
L103L104L0
L105L106L0
L107L108L0
L109L110L0
L111L112L0
L113L114L0
L115L116L0
L117L118L0
L119L120L0
L121L122L0
L123L124L0
L125L126L0
L127L128L0
L129L130L0
L131L132L0
L133L134L0
L135L136L0
L137L138L0
L139L140L0
L141L142L0
L143L144L0
L145L146L0
L147L148L0
L149L150L0
L151L152L0
L153L154L0
L155L156L0
L157L158L0
L159L160L0
L161L162L0
L163L164L0
L165L166L0
L167L168L0
L169L170L0
L171L172L0
L173L174L0
L175L176L0
L177L178L0
L179L180L0
L181L182L0
L183L184L0
L185L186L0
L187L188L0
L189L190L0
L191L192L0
L193L194L0
L195L196L0
L197L198L0
L199L200L0
L201L202L0
L203L204L0
L205L206L0
L207L208L0
L209L210L0
L211L212L0
L213L214L0
L215L216L0
L217L218L0
L219L220L0
L221L222L0
L223L224L0
L225L226L0
L227L228L0
L229L230L0
L231L232L0
L233L234L0
L235L236L0
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C   SAC CONTINUE
C   600 CONTINUE
C
C   CALCULATE PANEL FORCES
C
C   77C TABSPAN=50.01 GO TO 611
C
C   NO=6
C   NF=4
C   LTYP=1
C
C   00 775 1-1,6
C   00 775 4-1,10
C   775 C44,I=0,0
C
C   00 800 L101PAN
C   NP=5-LPI1L1
C   TFLNP-ME,M1 GO TO 800
C
C   XLSTL
C   ME=2,L1
C   JAPF=1,L1
C   NCAPP=12,L1
C   IF 4MC,EQ,0) GO TO 800
C
C   0-0,0
C   F=0 Q=0-B887 I=0,J
C
C   58-1L0-2COP4,ARC1,DCP11,MC1)/2-4
C   IF (B887 730,770,725
C   725 584,-OP11,ARC1,DCP11,MC1)/88
C   P1C COMM=2,002,COP11,ARC1,DCP11,MC1)/88
C   SA-COMM2,-881
C   SB-COMM1,-881
C   SC-CP11,MC1,CP12,MC1,MC1,CP13,MC1)/88
C
C   CALL TABT 12,54,58,SC,10,55,CA1
C
C   L101P1-M1
C   L101P1-M2-1
C   L101P1-M3-1
C   L101P1-M4-1
C   L101P1-M5-1
C   L101P1-M6-1
C
C   CALL TABW 12,54,58,FR,4NN,MED,PLD,MFO,L,3,1
C   IF INDIR=0,01 GO TO 38
C   CALL TABT 1FAC,CP12,MC1,CP11,ARC1,CP13,MC1)/88
C   LNL11-2988,0

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120 RETURN
END

SUBROUTINE TABST IF(AA4,AN,V,A1,DD,ML0,CON,ITAC)
C
C   CALCULATING STRESSES
C
DIMENSION F(10,ML0)
C
DATA TOL /1.E-8/
C
IF (ML0.EQ.0) GO TO 999
C
Z=0.
IF (DD.GT.TOL) Z=Z+.001/100
C
IF (ITAG.EQ.2) GO TO 200
C
IF (ITAG.EQ.21) GO TO 200
C
130 DO 10 L=1,ML0
IF (Z.LLE.0) GO TO 15
F15=L*F(1,1)+L*CON/11
F16=L*F(2,1)+L*CON/11
15 IF (A1.GT.-.03) F17=L*F(3,1)+CON/11
IF (A1.LT.-.03) F18=L*F(4,1)+CON/11
10 CONTINUE
GO TO 999
C
200 DO 20 L=1,ML0
IF (Z.LLE.0) GO TO 25
F16=L*F(1,1)+L*CON/11
F17=L*F(2,1)+L*CON/11
F18=L*F(3,1)+L*CON/11
25 IF (F18.LT.-.03) GO TO 20
F19=L*F(4,1)+CON/11
20 CONTINUE
999 RETURN
C
END

SUBROUTINE TABG (L,R,C,M1,M2,V1,V2,XL,ITAC)
C
RELEASED FIXED END FORCES FOR PINNED CONDITIONS
C

```



```

200 FIL,J=6,I,J=CALC,X(R,KK,J)
C
C CALCULATE DYNAMIC FUNCTIONS
C
      WRITE(6,100)
      IF (X(KK,J)=1) X(KK,J)=250.0
      DO 500 K=1,NK
      X(K,KK,J)=X(K,J)
      IF (X(K,J).NE.0) X(K,J)=X(K,J)-X(K,J)
      X(K,J)=X(K,J)/X(K,J)
      500 CONTINUE
      IF (X(KK,J).LT.350.) X(KK,J)=350.0
      350 F1=F1+X(KK,J)*X(KK,J)
      F1=F1+X(KK,J)*X(KK,J)
      S1=X(KK,J)*X(KK,J)
      GO TO 400
      350 IF (X(KK,J).EQ.0) F1=91.0
      F1=F1+91.0
      C1=C1+F1*X(KK,J)
      400 CONTINUE
      IF (X(KK,J).EQ.0) X(KK,J)=C1/100.0
      500 FIL,J=207,F1,J,3
      550 GU TO 999
      C
      PRINT* 'PREDICTOR FORCE FOR ALL LINES'
      C
      500 M1=N+1
      C
      WRITE(6,100)
      DO 600 I=L,L,D
      600 IF (L.GT.M1) GO TO 650
      LAND(I,M1)
      IF (I.EQ.L) GO TO 650
      DO 650 J=L,L,D
      650 IF (J.EQ.L) GO TO 650
      IF (I.EQ.J) GO TO 600
      IF (I.EQ.J-1) GO TO 600
      IF (I.EQ.J+1) GO TO 600
      IF (I.EQ.J-2) GO TO 600
      IF (I.EQ.J+2) GO TO 600
      600 CONTINUE
      END

```



```

C      00 300 I=1,NFF
IF (I1F1,I1M1,I1E1) GO TO 300
IF (I1N,I1C,I1F1,I1E1) GO TO 300
CALL MUDJ ABLIST1$1
IF (I1F1,I1M1,I1E1) GO TO 300
LINE=LINE+9
WRITE (IOUT,10001 SDIM,11
150 WRITE (IOUT,20001 FMED1,I,J=1,4),IV1,I,N,J,J=1,6)
100 CONTINUE
300 CONTINUE
C      RETURN
C      1000 FORMAT (//,S
        ,4SH SUMMARY OF STORY SHEAR DISTRIBUTION
        ,4SH STORY-BY-STORY / FRAME-BY-FRAME
        ,4SH SHEARLOAD2X1M/3X1M-LHM//)
        ,4SH 4XH02220H/---FRAME LOCATIONS--/
        ,4SH 8XH17XMM163M117X2M1V8XIMAXXH0)
2000 FORMAT (8X,45,0F9.2)
100C FORMAT (1H0,45,0F9.2)
END
C      SUBROUTINE FSCALE (SDIM,Y0,M1,MC,MS,NC,IF,ITAG)
C      PLOTTING FRAME ELEVATION
C      COPMPL PLOTS/ AD, Y0, MC, MS, SDIM, YD1M, YD1P, S1, B1, D1D
C      DIMENSION SDIM(11),Y1MS(11)
C      DIMENSION Y1MS(11),Y1MS(11)
C      IF (ITAG<0.2) GO TO 200
100 CALL FSCALE (SDIM,Y0,M1,MC,MS,NC,MS,IF)
CALL FCOD (MPC,SDIM,Y0,M1,MC,MS,NC,MS,IF)
GO TO 999
200 X0=0.
Y0=0.
CALL CALCM (I1D1M,6,0,B,R,4,-3,-1)
GO TO 999
C      SUBROUTINE FSCALE (SDIM,Y0,M1,MC,MS,NC,IF,ITAG)
CALCULATING SCALE OF SPAN ELEVATION PLOT
COMMON /PLOTS/ X0,Y0,DPM,DI1M,YD1P,S1,B1,D1D
DIMENSION SDIM(11),Y1MS(11)
DIMENSION SDIM(11),Y1MS(11)
C      1000 FORMAT (//,S
        ,4SH SUMMARY OF STORY SHEAR DISTRIBUTION
        ,4SH STORY-BY-STORY / FRAME-BY-FRAME
        ,4SH SHEARLOAD2X1M/3X1M-LHM//)
        ,4SH 4XH02220H/---FRAME LOCATIONS--/
        ,4SH 8XH17XMM163M117X2M1V8XIMAXXH0)
2000 FORMAT (8X,45,0F9.2)
100C FORMAT (1H0,45,0F9.2)
END
C      SUBROUTINE FSCALE (SDIM,Y0,M1,MC,MS,NC,IF,ITAG)
C      PLOTTING FRAME ELEVATION
C      COPMPL PLOTS/ AD, Y0, MC, MS, SDIM, YD1M, YD1P, S1, B1, D1D
C      DIMENSION SDIM(11),Y1MS(11)
C      DIMENSION Y1MS(11),Y1MS(11)
C      IF (ITAG>0.2) GO TO 200
100 CALL FSCALE (SDIM,Y0,M1,MC,MS,NC,MS,IF)
CALL FCOD (MPC,SDIM,Y0,M1,MC,MS,NC,MS,IF)
GO TO 999
200 X0=0.
Y0=0.
CALL CALCM (I1D1M,6,0,B,R,4,-3,-1)
GO TO 999
C      SUBROUTINE FSCALE (SDIM,Y0,M1,MC,MS,NC,IF,ITAG)
CALCULATING SCALE OF SPAN ELEVATION PLOT
COMMON /PLOTS/ X0,Y0,DPM,DI1M,YD1P,S1,B1,D1D

```



```

CALL CALCOM (X=5,Y=22,Z=8,0.,-1,3)
CALL CALCOM (X=5,Y=22,Z=8,0.,-1,3)
N=FLOAT(P)
CALL CALCOM (X=2.5,Y=2.5,Z=2.5,R=0.,-1,4)
C
IF (LIPLTME(2)= GO TO 777
N=FLOAT(D10))
X1=+5
Y1=+5
Z1=+5.52
CALL CALCOM (X1+7.5,Y1+0.,-1,3)
X1=+1.5
CALL CALCOM (X1+1.5,Y1+0.,-1,4)
C
777 CALL LYME (X1+52,Y1+52-Z1+5,Y1+2)
DXXXX
CALL CALCOM (X2+32,Y1+5,Z1+R,-90.,-1,3)
C
991 RETURN
C
END

```

YY=Y1+DY/A.

```

TAB580 4834
TAB580 4835
TAB580 4836
TAB580 4837 C
TAB580 4838
TAB580 4839
TAB580 4840
TAB580 4841
TAB580 4842
TAB580 4843
TAB580 4844
TAB580 4845
TAB580 4846
TAB580 4847
TAB580 4848
TAB580 4849
TAB580 4850
TAB580 4851
TAB580 4852
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TAB580 4920
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TAB580 4922
TAB580 4923
TAB580 4924
TAB580 4925

```

C=PI/2.0

```

SUBROUTINE FDOLC (X1,X2,Y1,Y2,W,JD,IPLY)
C
PLOTTING DIAGONALS
C
COPROM /PLOTS/ X0,Y0,Z0,RK,X0PN,X0IN,YDIM,S2,01,02,Q,RAD
C
DIMENSION X1(4),Y1(4)
DIMENSION JD(4)
C
DATA S /-10/
DATA D /1M0/
DATA T /1M7/
DATA TD /1E-10/
C
N=10(4)
N=22.
C
D1=-22.-1
D2=-22.-1
QL=SQRT(D1*D2)
THE=ATAN(DY/DX)
THE=THE*RAD
COST=D/VOL
SI=M-D/VOL
C
MM=XL*DX/A.

```

YY=Y1+DY/A.

```

TAB580 4834
TAB580 4835
TAB580 4836
TAB580 4837 C
TAB580 4838
TAB580 4839
TAB580 4840
TAB580 4841
TAB580 4842
TAB580 4843
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TAB580 4923
TAB580 4924
TAB580 4925

```


MAINROUTINE CALCS FREQS, DIPS, PANTS, DODE
SUBROUTINE CALLING CALCOMP PRINTING ROUTINES
SUBROUTINE PLOTS/40,40
SUBROUTINE 10111

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|--------|------|
| TAB580 | 5213 |
| TAB580 | 5215 |
| TAB580 | 5235 |
| TAB580 | 5236 |
| TAB580 | 5237 |
| TAB580 | 5238 |
| TAB580 | 5239 |
| TAB580 | 5240 |
| TAB580 | 5241 |
| TAB580 | 5242 |
| TAB580 | 5243 |

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Theoretical basis for CTABS80, a computer program
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